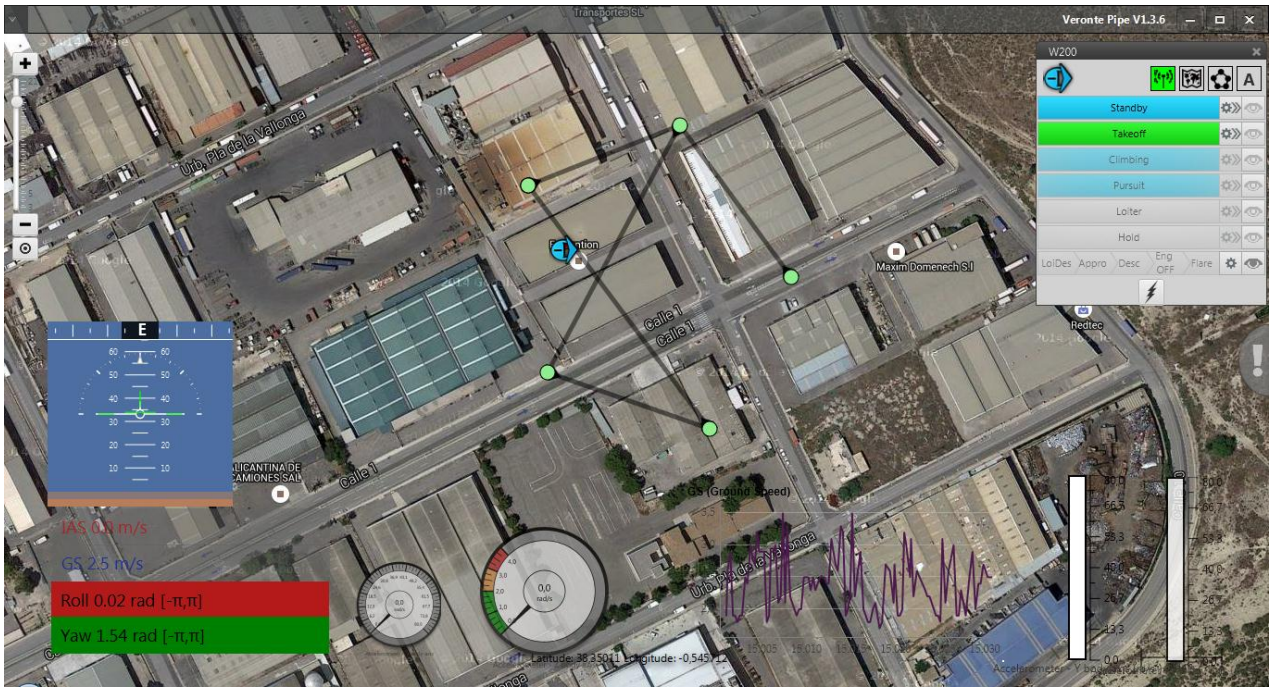
VERONTE

PIPE

Software User Manual



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Acronyms

HUM	Hardware User Manual
ID	Identification
PFD	Primary Flight Display
REC	Record
RPAS	Remotely Piloted Aircraft
SUM	Software User Manual
SRS	Software Requirements Specifications
UAV	Unmanned Aircraft Vehicle
WP	Waypoint

1. OVERVIEW

1.1. System Overview

Veronte Pipe is the software designed for operating any Veronte powered platform. Users achieve a combination of easy-to-use application, real-time response and, firstly, safe operations.

It has been developed using software standard model of IEEE STD 830-1998, Recommended Practice for Software Requirements Specifications (SRS) and STANAG 4671 documentation, subpart I about UAV Control Stations adapted to Veronte system.

Supported operations include:

Telemetry: View real time on-board UAV metrics, such as sensors, actuators and control states.
Telecommand: Support for all synchronous operator control commands that can be sent to the flight segment, e.g. operational mode switch, mission management, payload control and so on.
Mission design: Configure missions with waypoint definition, payload target definition and coverage analysis.
Mission analysis: Rebuild all recorded data from a previous flight and generate plots and reports.
Configuration: Edit RPAS settings, such as servo trim, interface/port management and so on.
Multiple Users: One or more operators can work simultaneously.

Veronte powered systems have two main elements, air and ground segments.

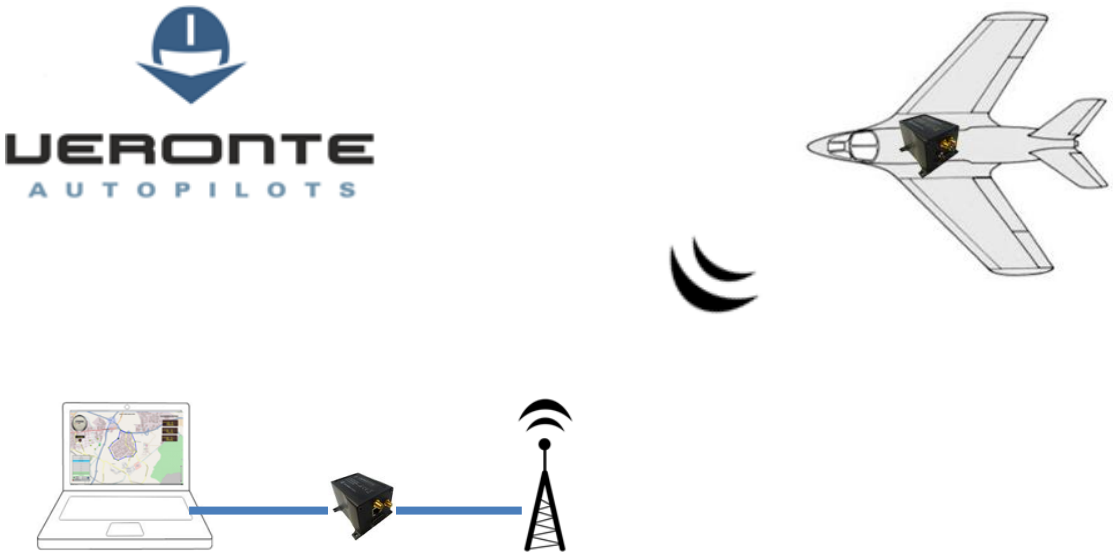


Figure 1: Veronte System Overview

Veronte onboard unit includes all necessary elements to; communicate with control station segment, take flight measures, control the aircraft and control the payload.

Veronte unit on the control station redirects stick and PC data to the onboard segment, and manages bidirectional communications between Veronte Pipe and the unmanned vehicle.

1.2. Veronte Pipe Interface

Workspace on Veronte Pipe is distributed as shown on Figure 2:

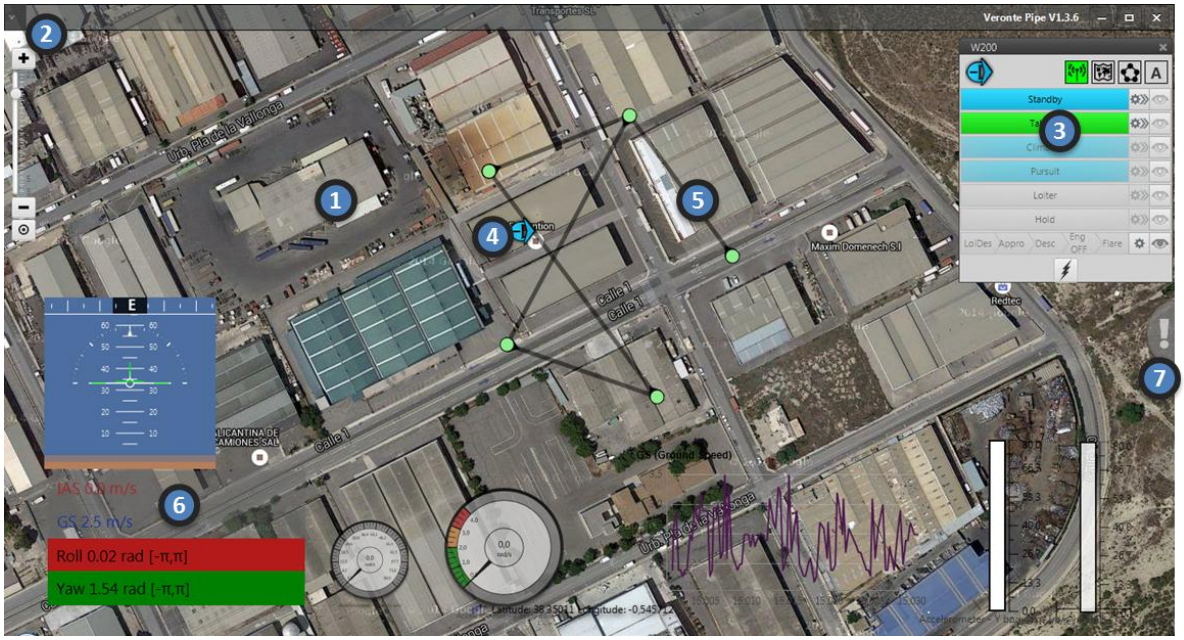


Figure 2: Interface

- **1:** Main display
- **2:** Menu
- **3:** Veronte Panel
- **4:** Veronte position
- **5:** Mission
- **6:** Telemetry displays
- **7:** Side panel

Each section has the following functions:

- **1 - Main Display:** Displays a selectable background map or a plain colour together with most important mission data.
- **2 - Menu:**
  - **User:** Manage user preferences.
  - **Setup:** Configure Pipe and Veronte autopilot.
  - **Workspace:** Select the way flight information is displayed.
  - **Mission:** Create and edit missions.
  - **Log:** View operation data log and introduce custom events.
  - **Post Flight:** Tools for recorded data analysis.
  - **License:** Manage license preferences.
  - **Help:** Shows help information available.
- **3 - Veronte Panel:** Veronte information and telecommand buttons.
- **4 - Veronte Position:** Veronte location on map
- **5 - Mission:** Defined mission on Veronte
- **6 - Telemetry:** Configurable drag & drop flight information displays.
- **7 - Side Panel:** Shows linked Veronte information.

Menu items are displayed as toolbars which can be pinned to the top bar or moved freely along the screen.

2. INSTALLATION

2.1. Veronte Pipe installation

To install Veronte Pipe just execute “Veronte_Pipe.exe” and follow the indications.

2.2. Update

Veronte checks for updates on system start up. A setup wizard will be displayed in order to guide the user on the update process. For manual updates follow the indications below.

⚠ **Caution!!** Although newer versions are usually compatible with older ones, when upgrading the system, updates must be done in the correct order. It is mandatory to update **Veronte Pipe** on first instance, **Veronte Onboard** second and last one should be the **Veronte on the Control Station**. Otherwise, part of the system could become unreachable.

⚠ **Caution!!** Never turn off Veronte during the update process. It could cause irreversible damage to the unit.

After installing las Veronte Pipe version, Veronte units on the side bar will be displayed as follows and Veronte compatibility alert will be displayed

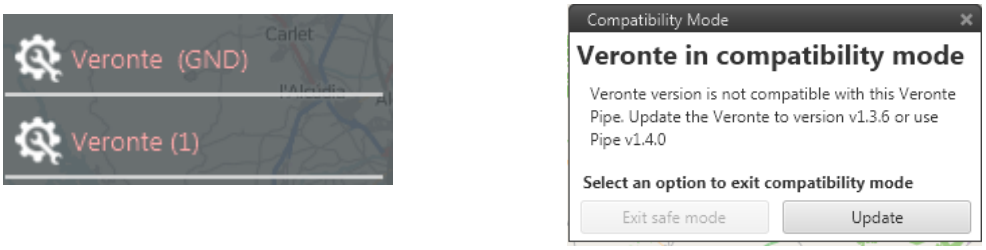
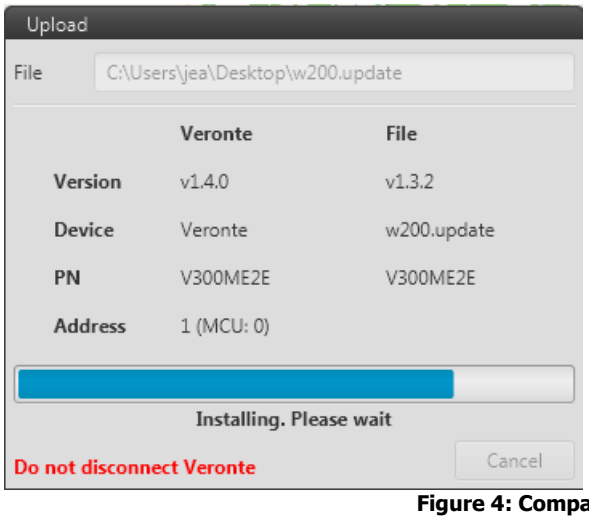

Veronte (GND)
Veronte (1)
Compatibility Mode
Veronte in compatibility mode
Veronte version is not compatible with this Veronte Pipe. Update the Veronte to version v1.3.6 or use Pipe v1.4.0
Select an option to exit compatibility mode
Exit safe mode
Update

Figure 3: Compatibility mode

In order to perform the update, click on update and press select the right update file for the Veronte unit you which to update. The upload process will start.



⚠ **Caution!!** During the update the system will reboot so never perform an update during an operation.

⚠ **Caution¡¡** Make sure you choose the right Veronte Update file for the selected Veronte Autopilot, otherwise unit recovery may be needed.

Figure 4: Compatibility mode

2.3. PC connection

Veronte unit on the control station must be connected to the same network than the pc running Veronte Pipe. In order to establish communications with Veronte, PC network interface IP must be in the same range than Veronte. IP can be changed in adapter settings in the Windows control panel, it must be set to IP: 192.168.137.XXX where XXX can be any number selected by user except from 106. Once the IP has been changed, network interface must be selected in Veronte Pipe preferences.

3. USERS

It is possible to define multiple users on Veronte Pipe, given the required permissions to each of them.

For each user it is possible to define read and write permissions for each toolbar, permitting or disabling access to each functionality on the system.

On first software run, it will start with the default user:

- User: admin
- Password: admin

Go to user toolbar in order to log out or manage users and passwords.

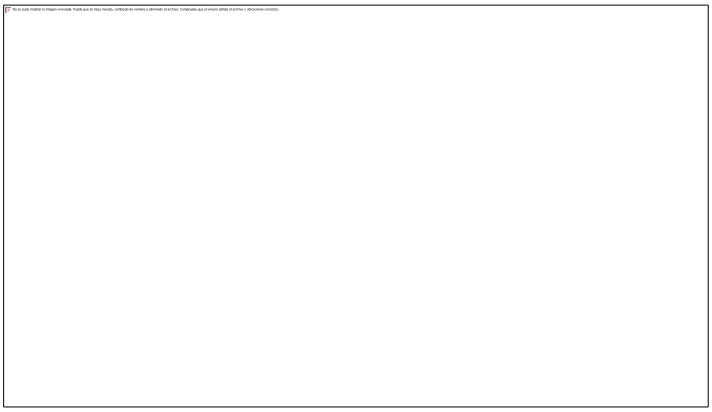


Figure 5: Login Screen

4. SETUP

In order to configure Veronte Pipe or any Veronte device, use the setup toolbar. Veronte Setup dialog can be opened on the main menu:

Figure 6: Setup Toolbar

	Details	Displays configurable fields.
	Open	Open Veronte configurations. Units connected to the PC will automatically be opened.
	Load	Select Veronte configuration to edit.
	Close	Close an opened Veronte configuration.
	Discard	Discard all changes.
	Save	Save all modified data.
	Import	Import a configuration form disk.
	Export	Export configuration on Veronte to disk
PLANE	**X-Plane**	Open X-Plane configuration. Refer to the HIL Simulator manual in order to configure the HIL parameters.
Tunnel UDP	**Tunnel UDP**	Select configuration of tunnel UDP. User can select IP and Port to send data from Veronte Pipe.

Table 1: Setup Toolbar

Configurable items are distributed on tabs, the following structure is followed:

Veronte autopilot:

Tab	Description
Veronte	Introduce Veronte information and aircraft layout.
Connections	Configure I/O connections on Veronte.
Devices	Configure any connected devices: servo, radio, camera...
Control	Introduce control variables or active adaptive control.
Modes	Manage flight modes and their parameters.
Navigation	Configure navigation parameters on the system.
Automation	Configure automatic actions on event detection (go home, turn on lights...).
Variables	Customize variable names and traffic: log, telemetry…
Panel	Configure Veronte Panel layout.
HIL	Configure parameters for Xplane Simulator

Table 2: Setup Tabs

Veronte Pipe:

Field	Description
Preferences	Veronte Pipe preferences
Units	Configure unit preferences

Table 3: Veronte Pipe Preferences

4.1. Veronte Pipe

4.1.1. Preferences

Veronte Pipe preferences permit to configure general application parameters. User must select the PC network interface used for interfacing with Veronte systems.

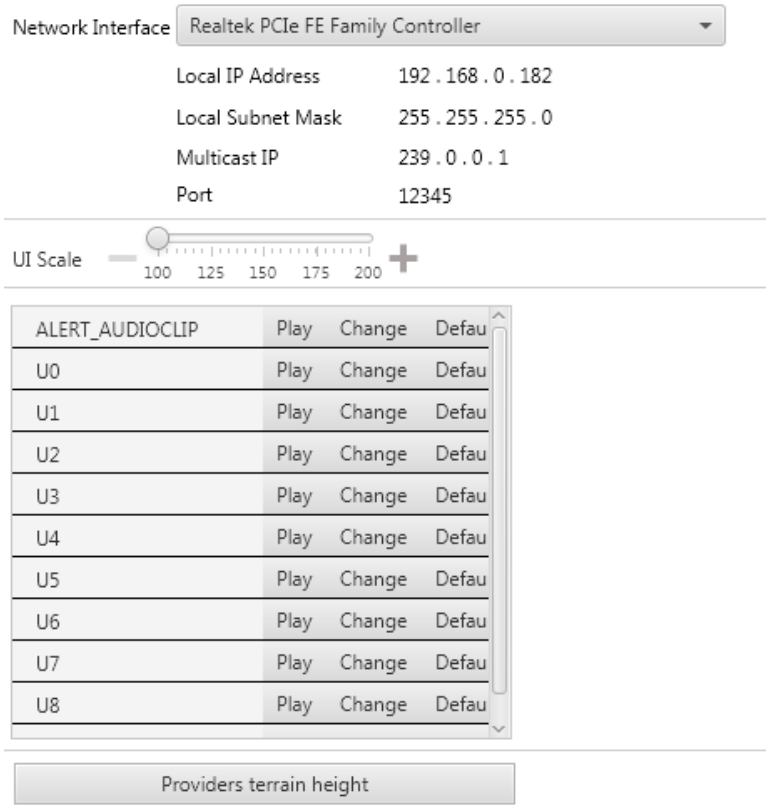


Figure 7: Veronte Pipe - Preferences

4.1.1.1. IU Scale

IU Scale permits to set the interface scale for adapting the application screen to the screen size on the system.

4.1.1.2. Alert Audioclips

Alert Audioclips is used for managing audio files used on the application. It can be associated to system alerts on the Workspace configuration.

4.1.1.3. Terrain Height

In order to perform the altitude estimation, Veronte installs a GIS (Geographic Information System). When creating a mission, the terrain altitude on the mission area is automatically downloaded from the internet. Once it is downloaded, this information will remain on the computer and no further internet connection will be needed.

In order to operate the system in zones without internet and where the mission cannot be created with an internet connection, it is possible to download the terrain information for a defined area. Just click on the areas of interest and it will light green as they are downloaded.

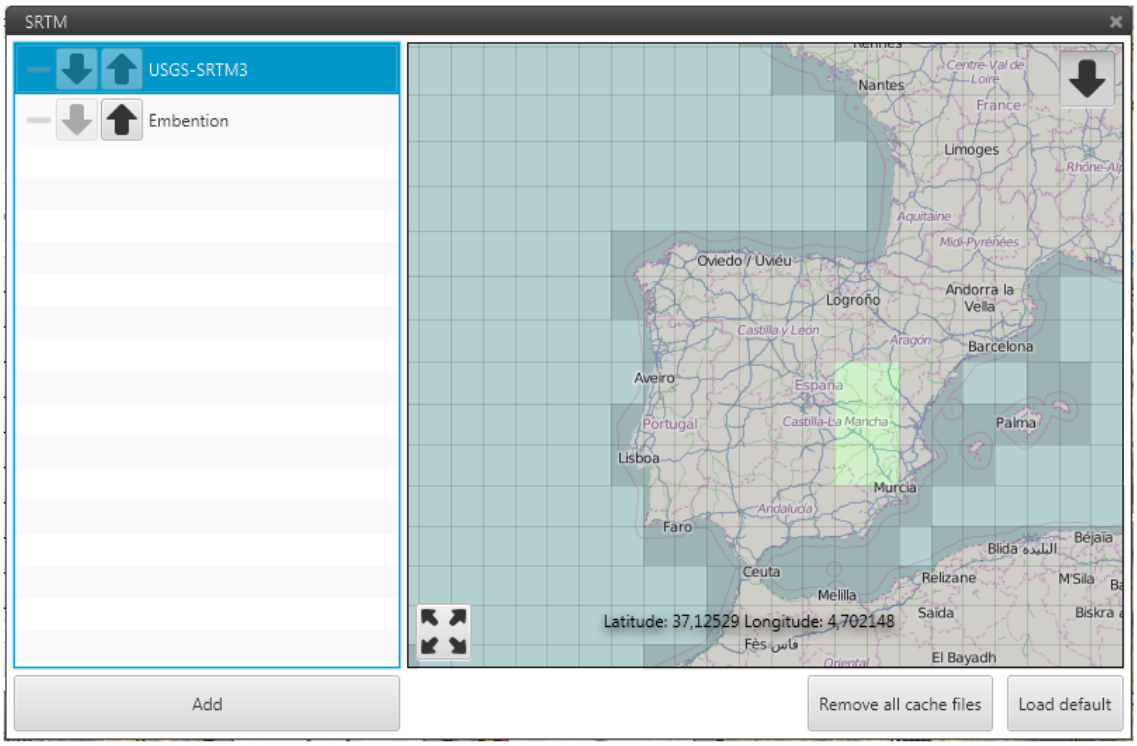


Figure 8: Veronte Pipe – Terrain height

User can include its own terrain providers to be used for flight altitude estimation. Click on add and enter required information for adding your own terrain altitude provider:

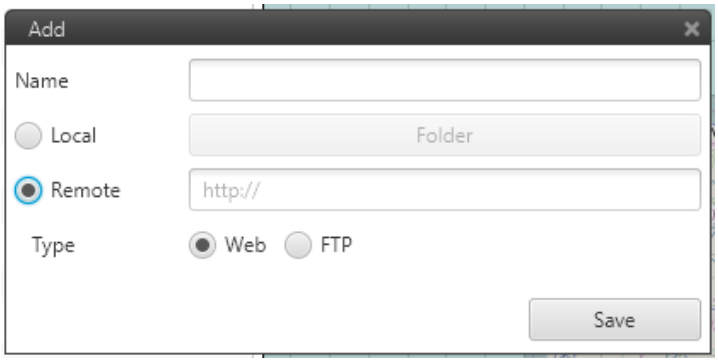


Figure 9: Veronte Pipe – Terrain height Add

4.1.2. Units

There is multiple system variables defined Veronte, arranged in categories. For each category, user can set as many custom units as desired by entering the corresponding conversion formula, adding multiple points on the graph.

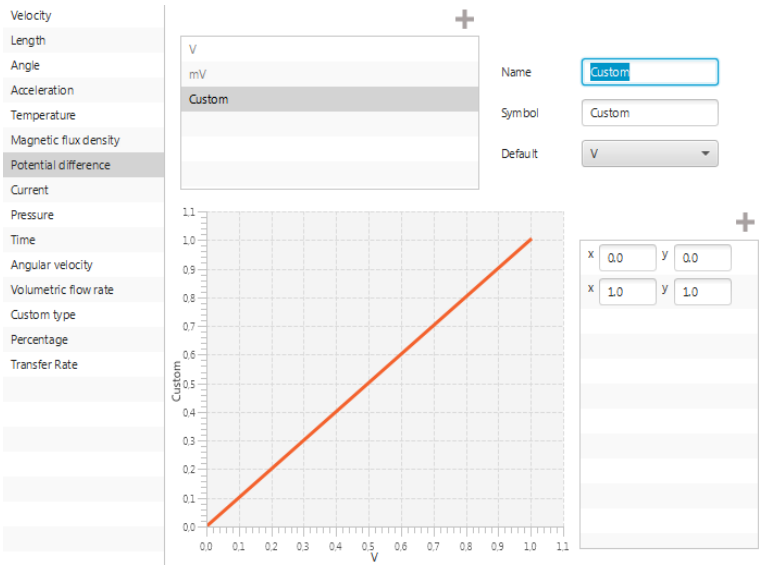


Figure 10: Veronte Pipe - Units

4.2. Veronte Autopilot

4.2.1. Veronte

Introduce Veronte identification and platform layout

Field	Description
Part Number	Introduce Veronte part number.
Aircraft	Aircraft name.
Address	Veronte unique identification number for datalink management.
ID	3 character ID for the platform.
Info	Information form the Veronte Unit
Type	Select platform type.

Table 4: Setup – Veronte

Once platform type is selected, layout must be entered so the system can be configured.

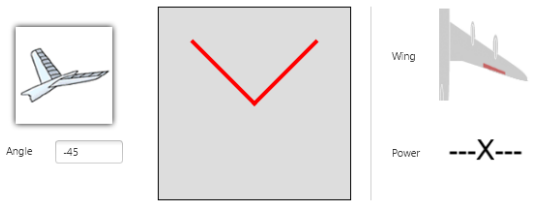
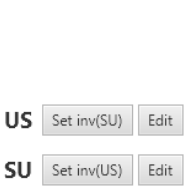


Figure 11: Setup - Veronte

For advanced platform configuration it is also possible to select custom type. US and SU matrix should be entered for configuring control output to actuators input.



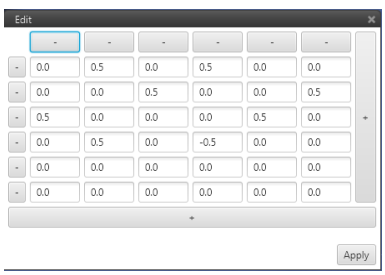


Figure 12: Setup – Veronte - Custom

S refers to actuators and U to control channels output. Set the actuator to control output in order to customize platform control.

On the SU matrix, rows refer to actuators and columns to control output. US matrix is the inverse matrix to SU, it can be automatically completed once the SU has been set by clicking on "Set inv (US)".

Veronte position within the aircraft must be entered by clicking in one axis and selecting the Veronte axis that corresponds to this direction. Veronte and GPS antenna distance to mass centre must also be entered.

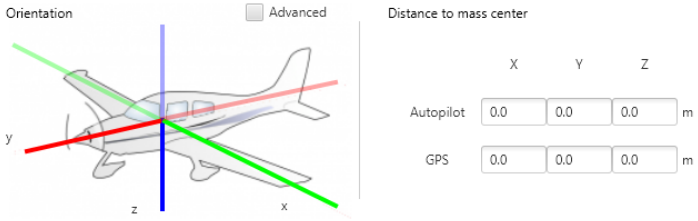
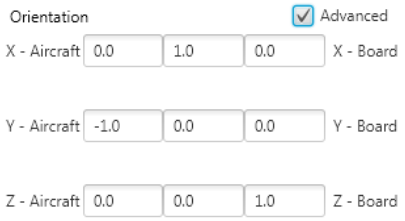


Figure 13: Setup – Veronte - Position



Advanced orientation configuration is also possible

Figure 14: Setup – Veronte – Advanced orientation

4.2.2. Connections

Connection tab permits to configure I/O ports on Veronte, by selecting the devices connected to each port and configuring the communications parameters.

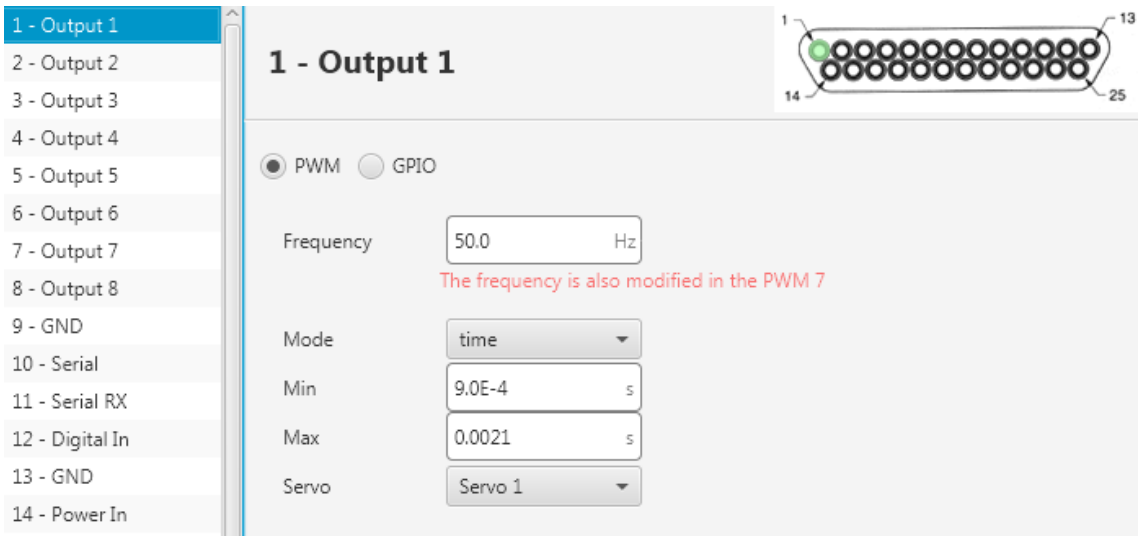


Figure 15: Setup – Veronte – Connections

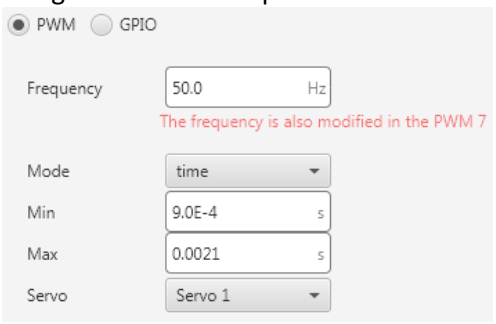
For each connector pin on Veronte, user is able to configure the following:

4.2.2.1. Output

System outputs, configurable as PWM or GPIO with following parameters

PWM:

Configurable PWM output.



- **Frequency:** Control frequency
- **Mode:** time / duty cicle / fixed
- **Min / Max:** output limits
- **Servo:** Select the actuator that is conencted

Figure 16: Output Configuration

GPIO:

Set output as a GPIO interface.

4.2.2.2. Serial

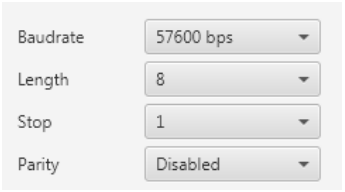
RS232 Port configuration, configurable as:

Radio:

External datalink radio connection. Fully compatible with radios not including communications protocol, output in one Veronte unit should be the input on the linked Veronte unit, ask for custom protocol configurations.

Tunnel:

Bidirectional tunnel between Veronte units.



- **Baudrate:** Communications baudrate.
- **Length:** Message length.
- **Stop:** Communications Stop.
- **Parity:** Message parity.

Figure 17: Tunnel

Magnetometer:

External magnetometer connection.

Transponder:

External transponder connection; fully compatible with Sagetch transponders, ask for compatibility with other systems.

Capture:

Capture port for input data

4.2.2.3. DIG IN

Digital input for custom sensor or payload connection.

Stick:

PPM joystick connection for platform or payload control.

Tunnel:

Digital input between Veronte units.

RPM:

RPM or similar sensor connection.

Varconsumer:

Connect any sensor or external device linking received data to a system variable.

4.2.2.4. ADC IN

Analog signal input or external battery voltage measurement.

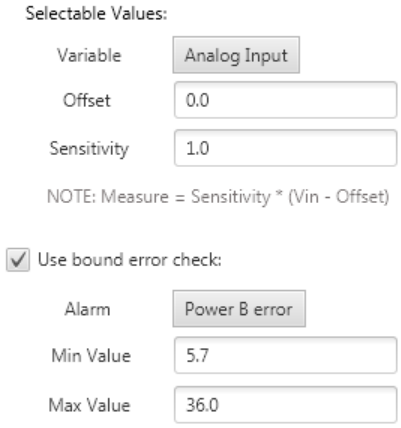


Figure 18: ADC IN

- **Selectable values:** Linked system variable
  - Measure = Sensivity x (Vin – Offset)
- **Bound error:** Link system error to input data
  - Choose alarm and limit values

4.2.2.5. CAN

CAN bus configuration

Configuration:

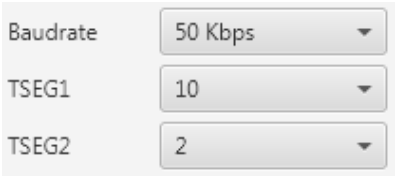


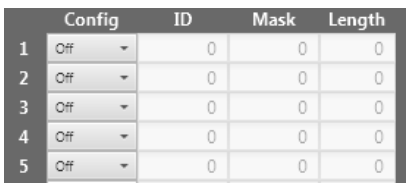
Figure 19: CAN

- **Baudrate:** Global configuration baudrate
- **TSEG1:** Time segment 1
- **TSEG2:** Time segment 2

These values should only be changed by experienced users, default values are as shown on the picture.

Mailboxes:

Up to 32 mailboxes can be configured for message transmission and reception.



- **Config:** Mailbox type
  - TX: Transmission mailbox
  - RX: Reception mailbox
  - RXO: Reception overwrite mailbox
- **ID:** 11 bit message TX or RX ID (decimal)
- **Mask:** mask filter for RX messages (decimal)

Figure 20: CAN - Mailboxes

- **Lenght:** Message size in bytes (1 to 8)

- **Transmission:** TX mailboxes should be configured in order to permit the message transmission trough the CAN port. Messages will be transmitted with the configured ID and size.
- **Reception:** Received messages will be stored on RX mailboxes until this data is written on a consumer. Any incoming message received after configured mailboxes are full will be discarded. In case RXO mailbox has been configured, new incoming messages for this ID will be overwritten on the defined mailbox.
- **Mask:** This filter is configured for reception messages; received data will be stored on mailboxes where message ID coincides with mailbox ID. Mask ads some flexibility on the reception, when comparing message with mailbox data, only binary digits configured as 0 on the mask will be taken into account. (Ex.: For a configuration MASK: **00**111 and ID:**10**110 all incoming messages addressed to **10**XXX will be received on this mailbox).
- **Overwrite:** When storing data on mailboxes it is done on decreasing order, form 32 to 1. When using multiple mailboxes with same ID and one of them is RXO, it is recommended to set this mailbox on the lower mailbox position, otherwise all messages received for this ID will be overwritten on the same mailbox, not filling the buffer.

Filter:

Filter is used for configuring system consumers. These parameters should only be edited form experienced users.

Figure 21: CAN filter

- **Packet 64:** Veronte to Veronte communications trough CAN configuration.
- **Simulation:** HIL simulation configuration.
- **Radar Altimeter:** Configuration for Smart Micro radar altimeters.

Telemetry:

Interactions between system variables and CAN variables are managed form the telemetry configuration.

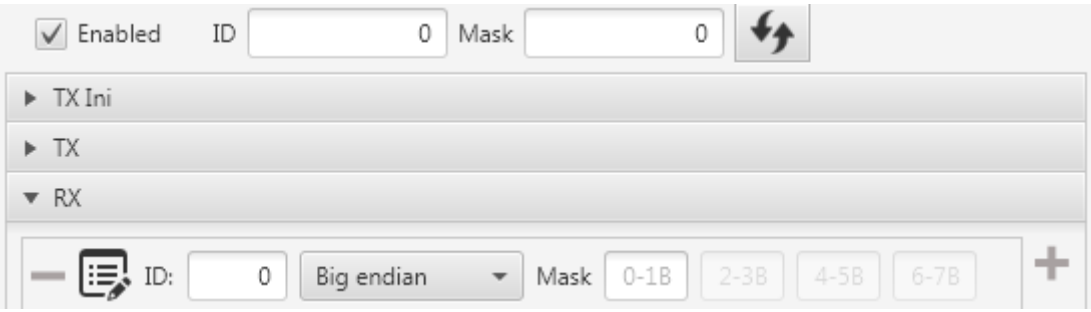


Figure 22: CAN - Telemetry

ID & Mask configuration sets the RX parameters for CAN telemetry. Only messages with an ID inside the configured range will be taken into account on the system.

System telemetry messages are divided on 3 groups.

- **TX:** Transmission messages, for data that autopilot will send periodically.
  - ***Period:*** Data transmission frequency.
  - ***Variables:*** System variables to be sent trough the CAN network.
  - ***ID:*** 11 bits CAN ID.
  - ***Endian:*** Big or little endian.
  - ***Decimation:*** Decimation over global tx frequency. Ex.: for a 0.1 period and a 3 decimation, messages will be transmitted in periods of 0.3s.
  - ***Offset:*** A divider from decimation. Ex.: for a period of 0.1, a decimation value of 3 and an offset of 2, messages will be sent each 0.3s starting on the 0.2s
- **TX Ini:** Initialization transmission messages, usually used to send initialization/setup commands to CAN devices at startup.
  - ***Variables:*** Associated system variables.
  - ***ID:*** 11 bits CAN ID.
  - ***Endian:*** Big or little endian.
  - ***Delay:*** Decimation value in which the message is sent. Delay is configured form the previous message, not from the system startup.
- **RX:** for data that will be parsed, writing any variable received form CAN on a system variable.
  - ***Variables:*** System variable to overwrite.
  - ***ID:*** 11 bits CAN ID.
  - ***Endian:*** Big or little endian.
  - ***Mask:*** Filters messages from message content. Enter headboard data that filters from data coming to the configured ID.

4.2.3. Devices

Devices panel permits to configure any device (payload, sensors…) connected to Veronte and the internal Veronte ones.

4.2.3.1. Veronte

Frequency:

Working frequencies on Veronte Autopilot

Figure 23: Setup – Devices – Frequency

Type	Description
OS	Operative System working frequency
Low	Low priority tasks, mainly for telemetry, other operations…
High	Working frequency for GNC tasks
Super High	Sensor capture and high priority tasks frequency

Table 5: Setup –Devices –Frequency

Ethernet:

For Veronte units equipped with Ethernet board it is possible to configure Ethernet parameters.

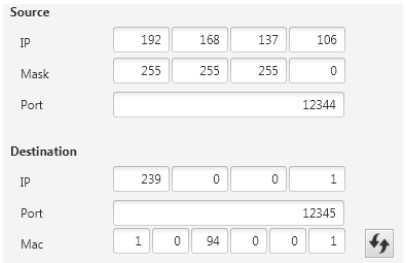


Figure 24: Setup – Devices - Ethernet

4.2.3.2. Control

Actuators:

Calibration interface for connected actuators. On this panel it is possible to set actuator position for ach control signal output, permitting to configure the maximum and minimum values and custom performance.

Figure 25: Setup – Devices - Actuators

Field	Description
Move To Startup	Move actuator to startup defined value.
Move to current value	Move actuator display to actuator output that is being currently commanded.
A	Refers to each actuator on the system. • Mark the checkbox and move the bar in order to move the connected actuator • Red zones are outside actuator limits. In order to move the signal outside these limits, mark the “Allow command Out of Limits” option.

U	Refers to the control channels configured on the system. Each control channel can be linked to multiple actuators. • When moving a control channel bar, box checked servos will move
Disable Servo	On first system configuration servos are disabled so no output signal is commanded. Once servo has been configured, default initiation position for servo is the defined start up value.
Start Up	Enter servo startup value, preferred position on system initialization
Acceleration	Acceleration limits on the actuator movement
S & Pulse	Draw as many points as needed in order to setup servo limits, assigning system pulse value to an actuator position (s)

Table 6: Setup – Devices - Actuators

Configuration Wizard:

Configuration wizard is recommended on first system configuration. It guides the user for configuring actuator limits and performance.

1 – Limits: Set maximum and minimum pulse value for the mechanical limits on the actuator.

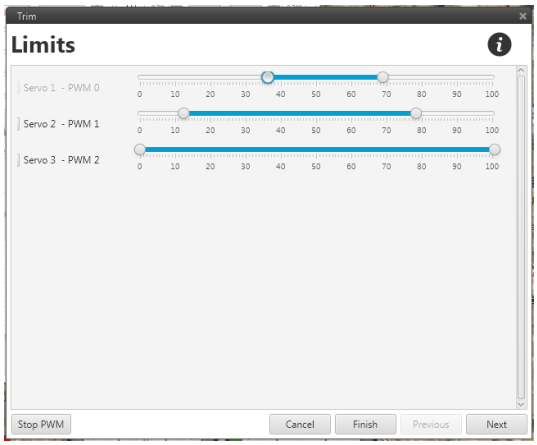


Figure 26: Setup – Devices – Actuators – Trim wizard 1

2 – Neutral: Set neutral position for actuators and control channels. To be used on startup and as a reference on trim. Box check to enable servo movement with the bar.

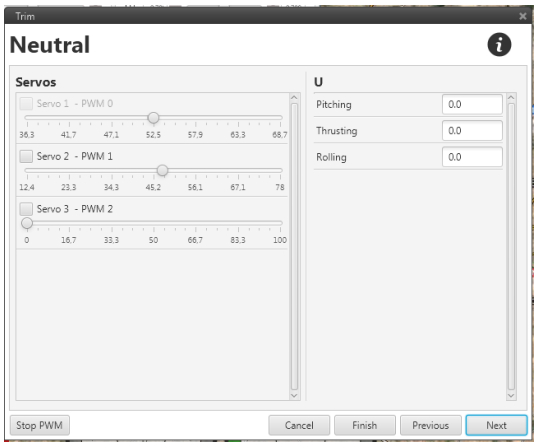


Figure 27: Setup – Devices – Actuators – Trim wizard 2

3 – Select: Select a servo to trim.

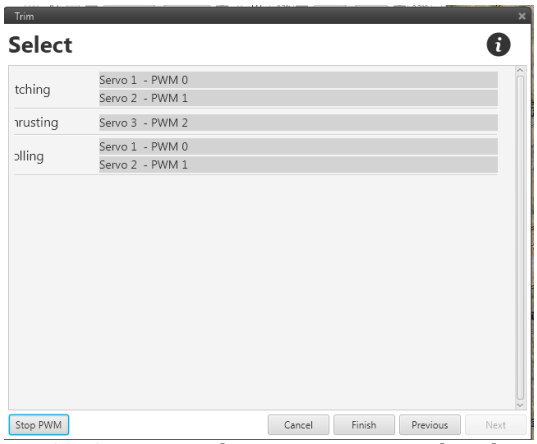


Figure 28: Setup – Devices – Actuators – Trim wizard 3

4 – Value: Enter maximum and minimum actuator position for the control variable.

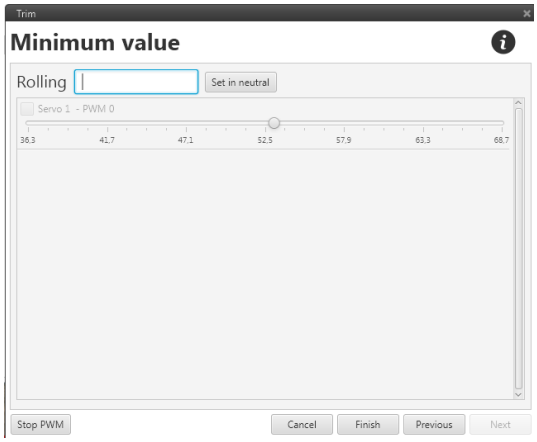


Figure 29: Setup – Devices – Actuators – Trim wizard 4

Advanced Configuration:

Actuator position is given as an "S" parameter which refers to the control variable associated to the actuator. Default units given are:

- Control surfaces (aileron, rudder...): Angle (in radians).
- Motor: Value between 0 and 1 where 1 is max power and 0 is the point where the motor starts the moving.

For "0" motor position it is recommended to set a 5% signal margin in order to make sure that the motor fully stops in all configurations.

Actuator positions must be given according to the international aeronautical sign convention:

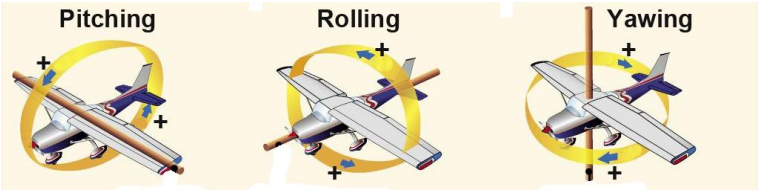


Figure 30: Sign Convention

Example, an elevator down position will generate a positive pitch so the elevator is considered positive on down position. Main actuators rules:

Actuator	Positive	Negative
Elevator	Down	Up
Rudder	Right	Left
Right Aileron	Up	Down
Left Aileron	Down	Up

Table 7: Actuator Configuration

⚠ **Note:** Maximum and minimum values must be set according to physical actuator limits. Configured limits will never be exceeded by the system in any flight mode.

4.2.3.3. Sensors

Encoder

Configure connected encoders on Veronte; draw as many points as needed in order to correlate the encoder input data on Veronte to the desired value on system.

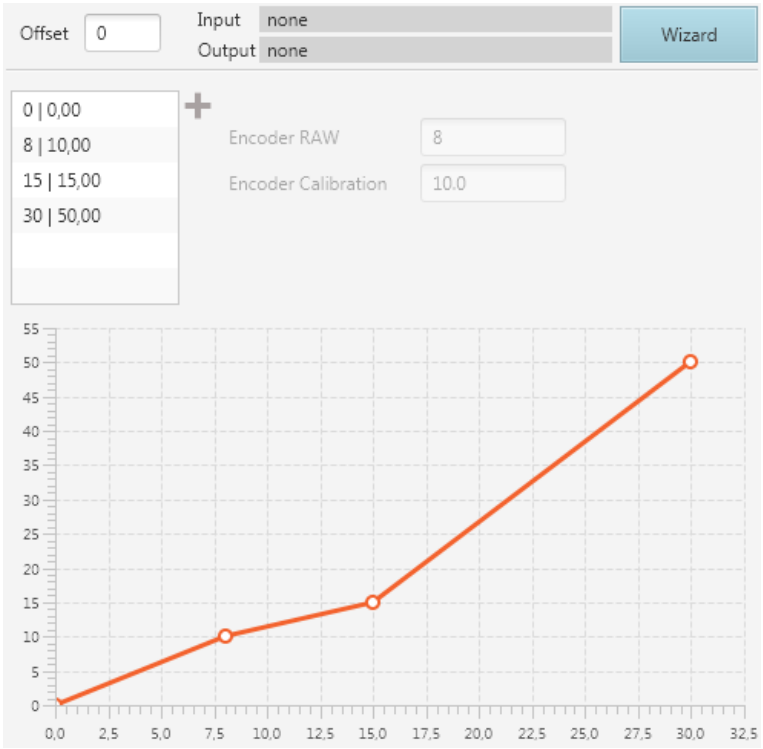


Figure 31: Setup – Devices –Encoder

Field	Description
Offset	The entire graph will be displaced the offset value
Graph points	Draw as many points as required for calibrating encoder performance • **Encoder RAW:** Real encoder captured data • **Encoder Calibration:** S value corresponding to the encoder data
UVar	Input variable for the encoder
RVar	Output variable for the encoder data

Table 8: Setup – Devices -Encoder

The calibration wizard can also be used for calibrating encoders. Follow the described steps for performing the calibration.

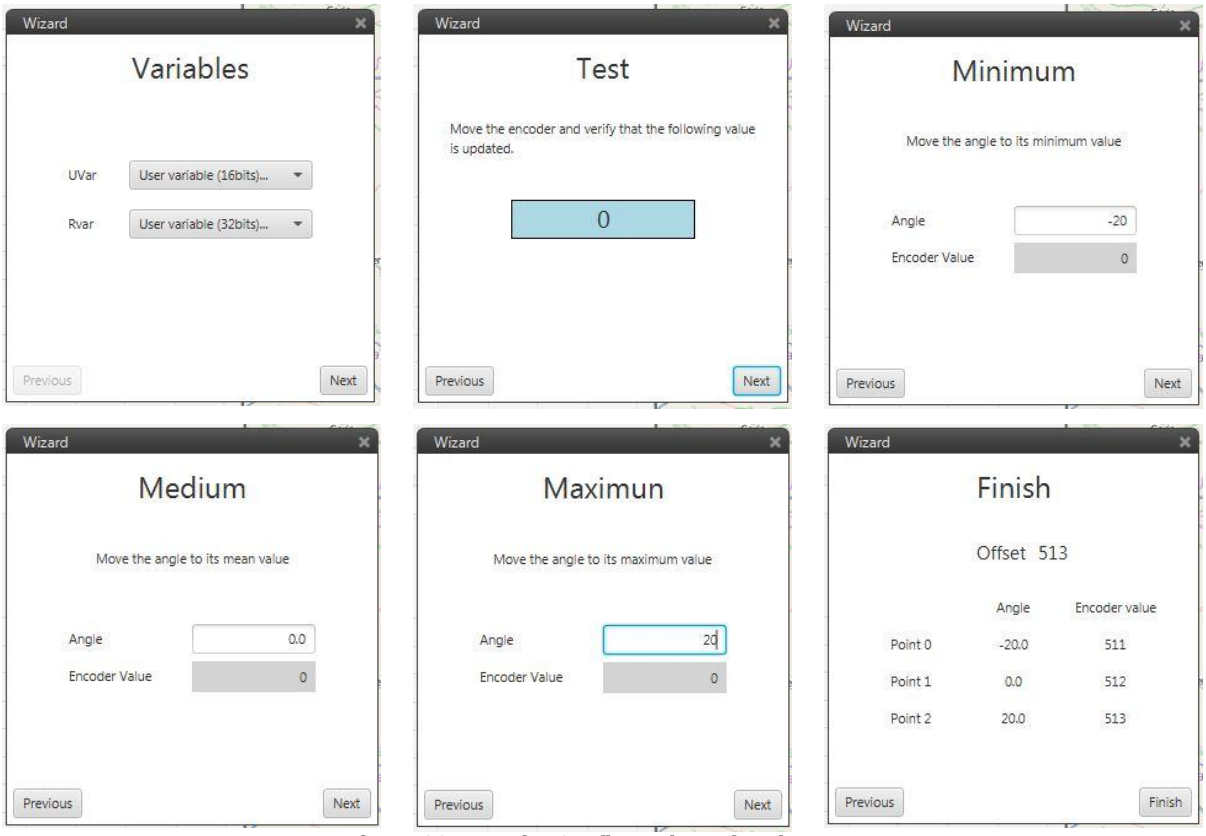


Figure 32: Encoder Configuration Wizard

Magneto Calibration

Magnetometer calibration should be performed once Veronte has been installed on the platform so the magnetic field during the operation is similar to the one measured during the calibration.

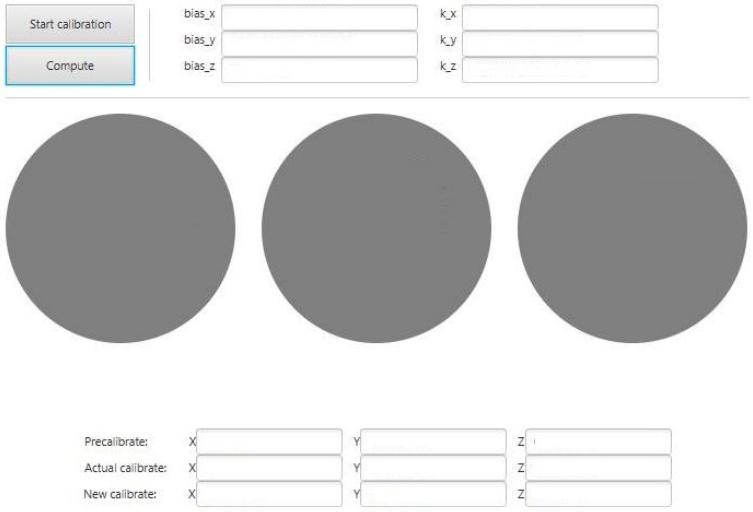


Figure 33: Setup – Devices – Sensor – Encoder

⚠ **Note:** Before initiating the calibration make sure that the following variables are active on telemetry (Setup – variables – telemetry – data link): "Magneto x", "Magneto y", "Magneto z"

In order to start calibration, press on the “Start Calibration” button so the system can capture magnetometer data. During the calibration the system must be oriented in all possible directions so enough data can be captured. Once enough data has been captured, “Compute Data” sets the calibration.

The procedure for acquiring enough data for performing the calibration is:

- Hold the platform with your hands on the “Y” axis and rotate it parallel to ground.
- While the platform is rotating, rotate also yourself so the platform turns in two axes simultaneously.
- Turn the platform 90 degrees within your hands and repeat the operation.

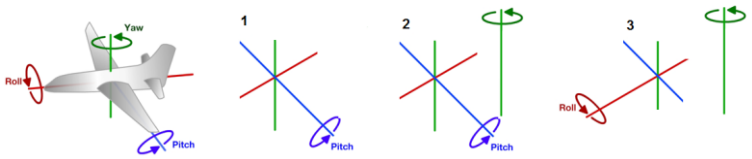


Figure 34: magnetometer calibration procedure

Once three circles have been drawn on the screen, captured data will be enough for saving the calibration data. The following image shows an example of the calibration result:

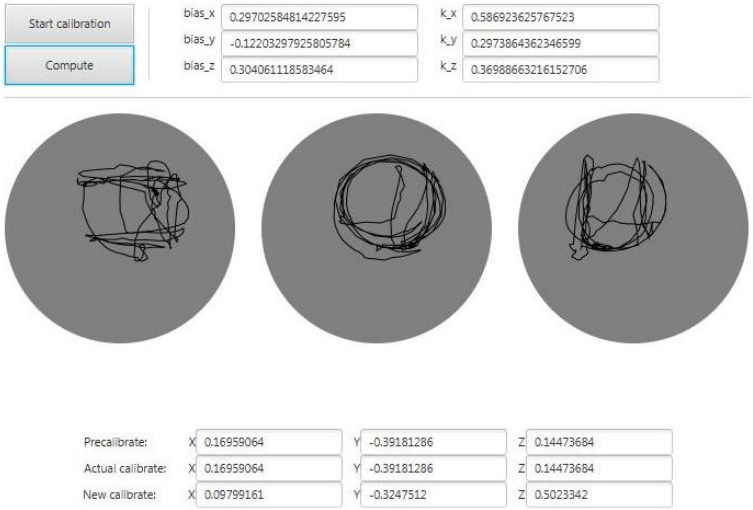


Figure 35: magnetometer calibration values

Magneto Navigation

Enable or disable magneto for navigation and configure magnetometer parameters.

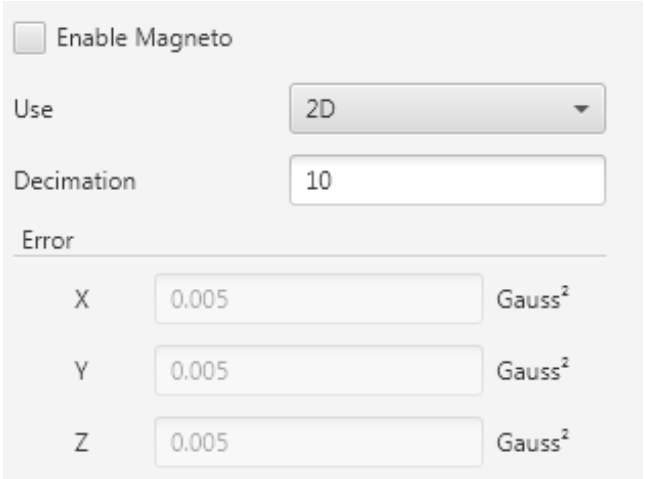


Figure 36: Setup – Devices –Magneto Navigation

Field	Description
Use	Choose angles for magnetometer use • **2D:** Only use horizontal measure for navigation • **3D:** Use 3 measures for navigation
Decimation	Magnetometer decimation
Error	Magnetometer error

Table 9: Setup – Devices –Magneto Navigation

Stick PPM

Configuration for the joystick connected through the PPM port.

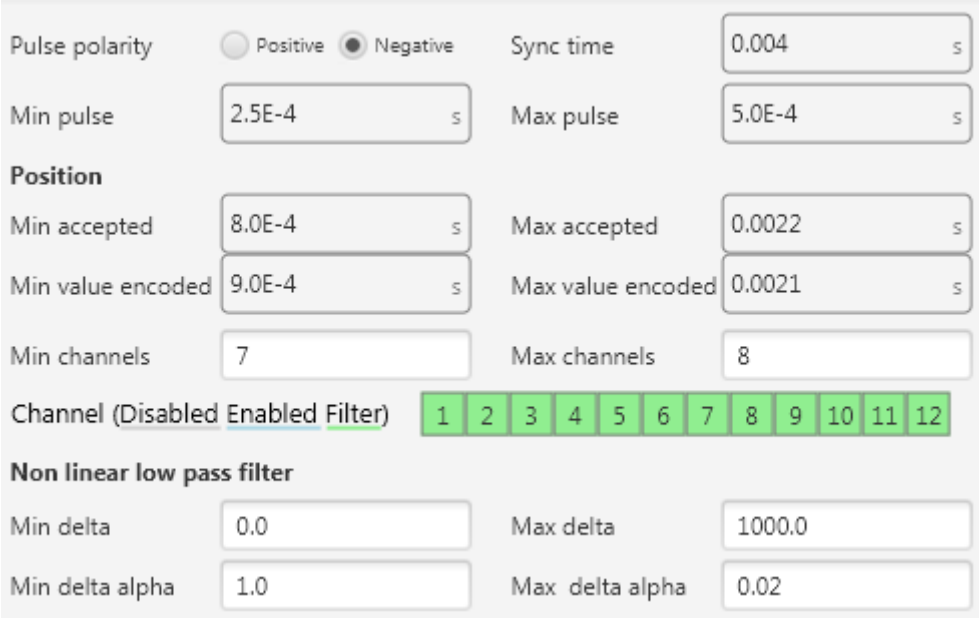


Table 10: Setup – Devices –Stick PPM

Dynamic Pressure

Configure dynamic pressure sensor input in Veronte

Figure 37: Setup – Devices – Dynamic Pressure

Field	Description
Type	Choose the dynamic sensor pressure use on the system • **Disabled:** Do not use dynamic pressure sensor for navigation • **Custom Settings:** Use sensor with custom settings • **Autocalibrated Variance:** Use sensor with automatic settings
Square Error	Sensor error

Decimation	Sensor decimation
Min. Pressure	Minimum pressure readable by sensor
Pitot Orientation	Pitot orientation on platform

Table 11: Setup – Devices – Dynamic Pressure

Radar Altimeter

Radaraltimeter settings, ask for compatible radaraltimeter options.

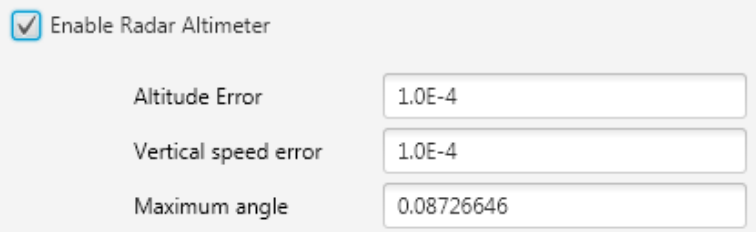


Figure 38: Setup – Devices – Radar Altimeter

Transponder

Veronte is fully compatible with Sagetech transponders, permitting to configure it from the user interface. Configurable parameters are displayed on the Transponder configuration panel; please refer to Sagetech transponder manual for further detail on the use of such variables.

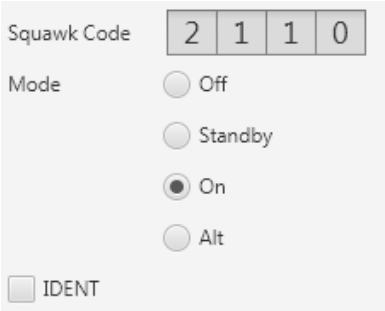


Figure 39: Setup – Devices – Transponder

Ublox GPS

Configure GPS sensor options, only for advanced users.

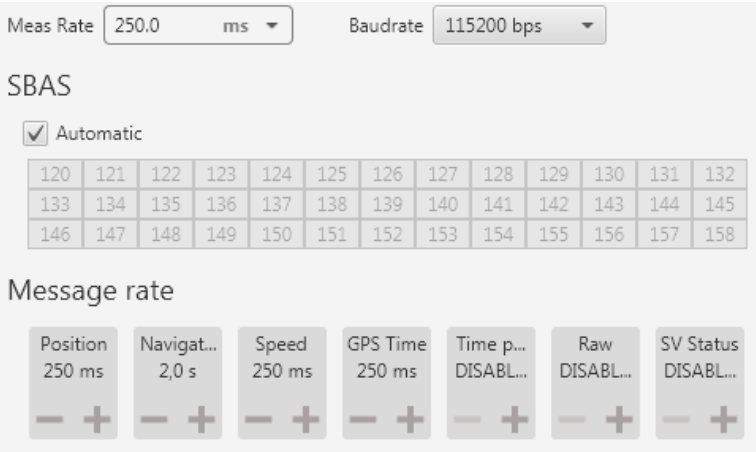


Figure 40: Setup – Devices –GPS

Static Pressure

Configure static pressure sensor use on the system.

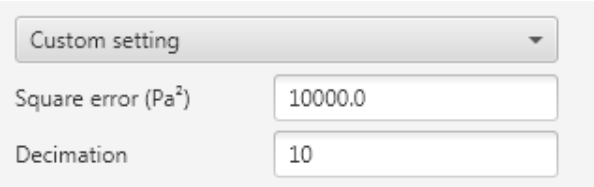


Figure 41: Setup – Devices –Static Pressure

Field	Description
Type	Choose the static sensor pressure use on the system • **Disabled:** Do not use static pressure sensor for navigation • **Custom Settings:** Use sensor with custom settings • **Autocalibrated Variance:** Use sensor with automatic settings
Square Error	Sensor error
Decimation	Sensor decimation

Table 12: Setup – Devices – Static Pressure

GPS

Configure GPS parameters to work for navigation or for differential GPS.

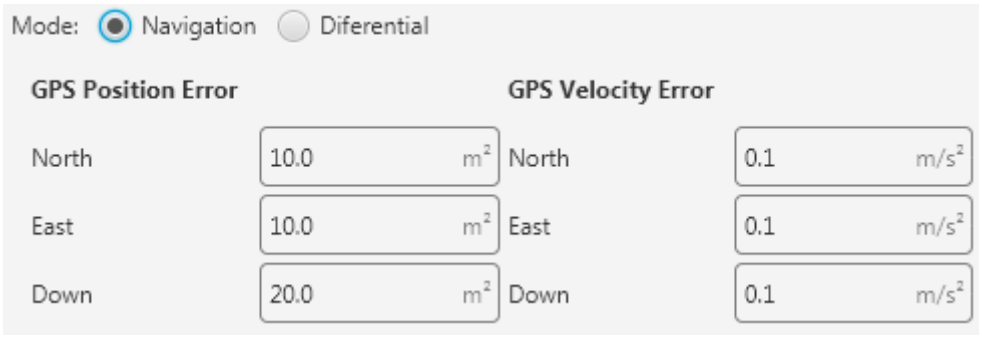

Mode: Navigation Diferential
GPS Position Error
GPS Velocity Error
North 10.0 m² North 0.1 m/s²
East 10.0 m² East 0.1 m/s²
Down 20.0 m² Down 0.1 m/s²

Table 13: Setup – Devices – GPS- Navigation

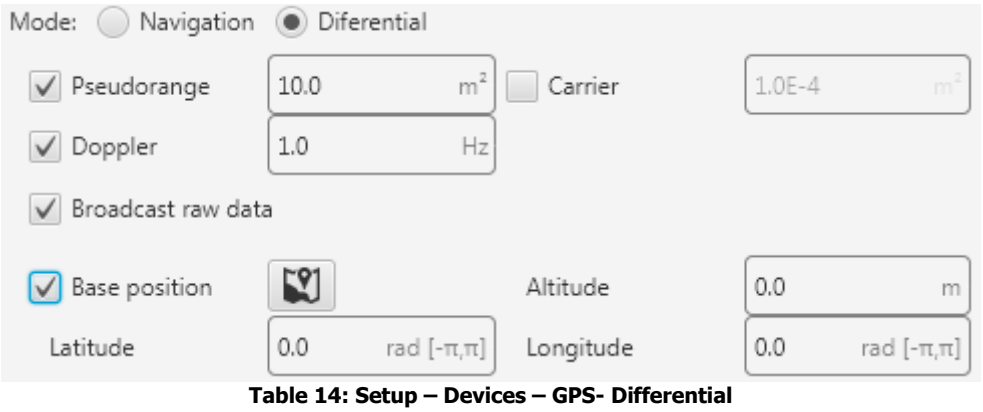


Table 14: Setup – Devices – GPS- Differential

4.2.3.4. Stick

Test Stick

For each stick channel configured, user can set continuous movement commands to be performed. For configuring the stick select the wave type and enter the requested parameters.

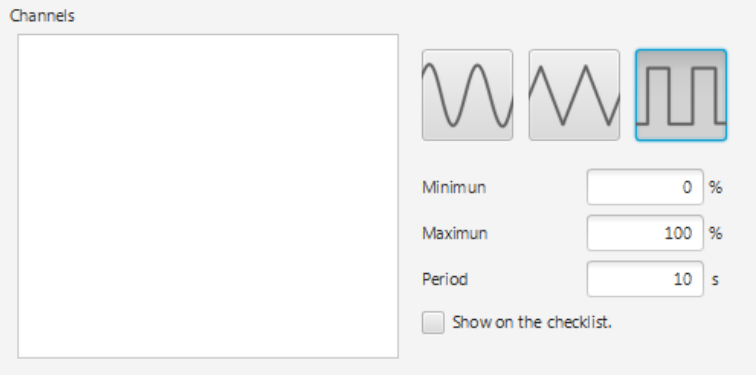


Figure 42: Test Stick Configuration

Configured parameters can be shown on the checklist in order to test the system prior to change flight phase.

To activate the automatic movement, use the activation button on the virtual stick configured on the workspace.

Stick

Configure stick parameters for manual and assisted manual system control.

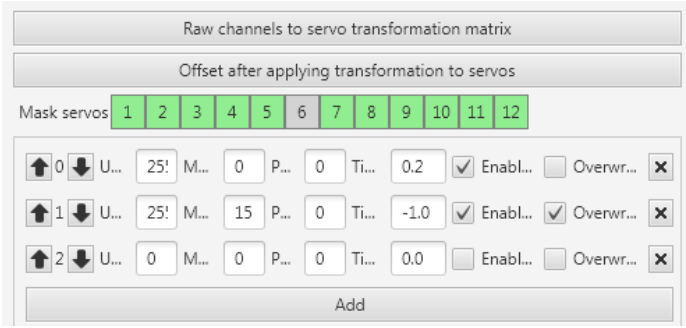


Figure 43: Stick Configuration

Use the raw channels to servo transformation matrix in order to make virtual servo missing and for customizing servo outputs.

Offset value will be added to output once the transformation is performed.

Click on “Mask Servos” in order to disable the stick control over those actuators.

It is possible to set multiple joystick inputs with the respective priority, from top to bottom.

UAV, MCU & Port refers to the Veronte unit where servo is connected, time is the time without reception to change to the following input. Enable enables receiving data from that stick and overwrite permits to have multiple inputs for different channels.

Virtual Stick

Configure virtual sticks on the system, select an input variable containing the stick data and select the Veronte unit destination to control.

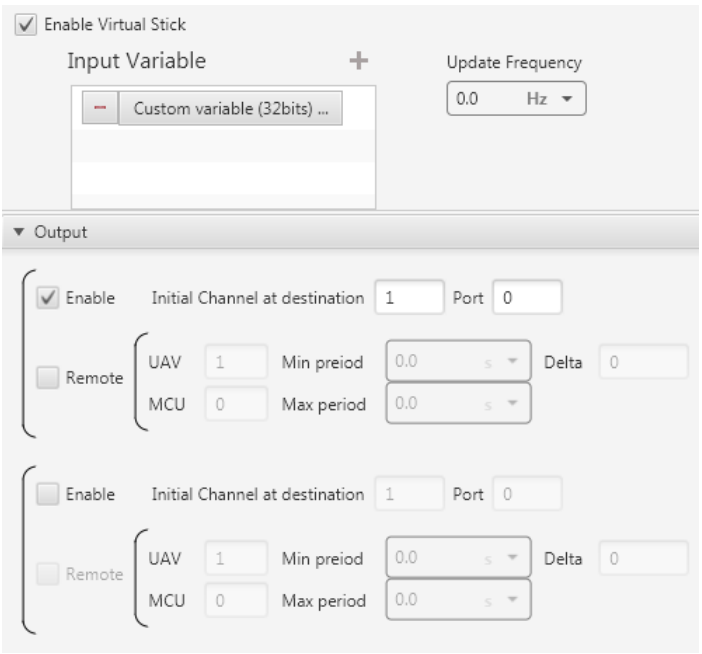


Figure 44: Virtual Stick Configuration

4.2.3.5. Micro

GPIO Manager

Enable or disable ports at microprocessor level.

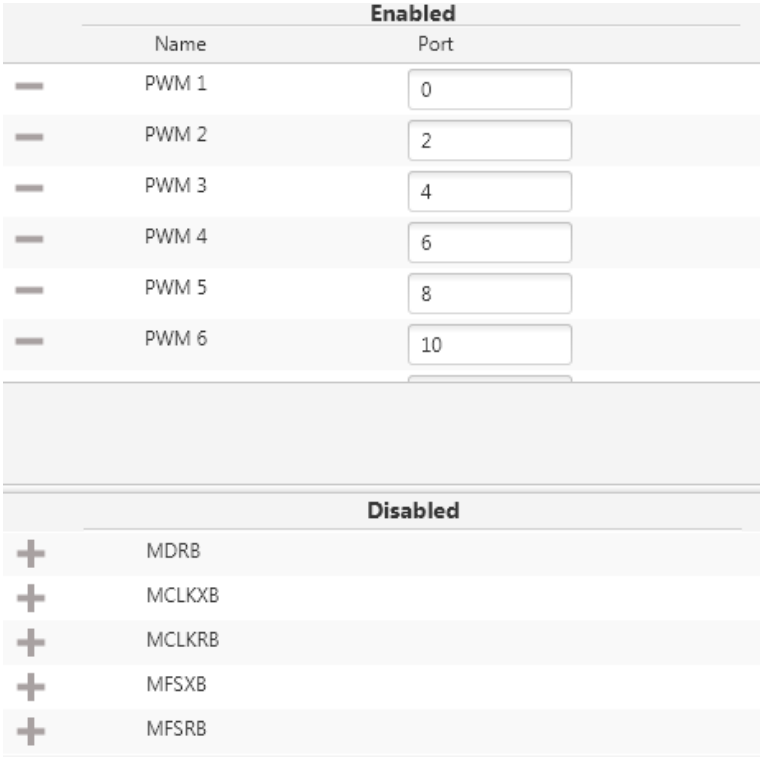


Figure 45: GPIO Manager

4.2.3.6. Others

Radio

Configure radio settings.

Payload

Configure connected gimbal settings, including number of gimbal axis, servos used for gimbal connection and distance from the autopilot to the Gimbal.

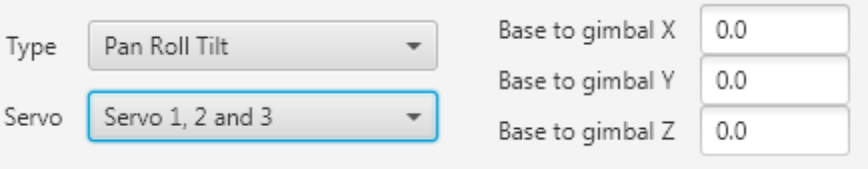


Figure 46: Payload configuration

4.2.4. Control

User can configure platform control parameters for setting the unmanned system performance during the operation.

⚠ **Caution:** Only for experienced users

On the left side of the Control interface, user can enter as many control phases as needed. A control phase refers to a set of specific control parameters defined for a concrete operation step (take off, waypoint route, hover…). Control parameters will be defined for each phase; user will be able to set automatic phase switch (on automation display) or use manual switch on Veronte Panel.

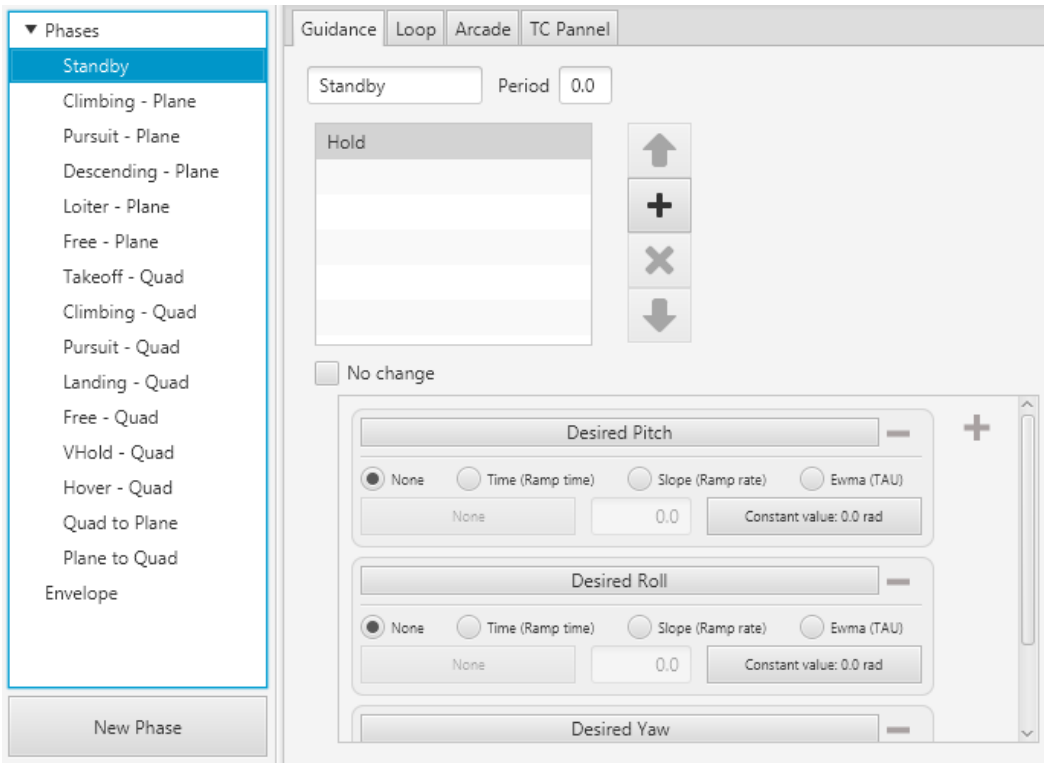


Figure 47: Setup - Control

For each phase user must configure three main elements:

Value	Description
Guidance	Select guidance type and main parameters
Loop	Set control loops
Arcade	Configure arcade mode for assisted manual control

TC Panel	Configure lateral slider options on the Veronte Panel

Table 15: Setup Control

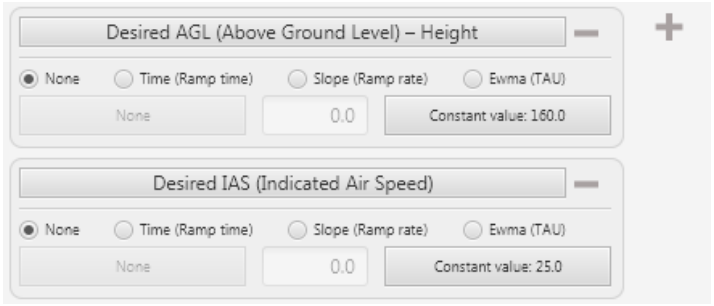
4.2.4.1. Guidance

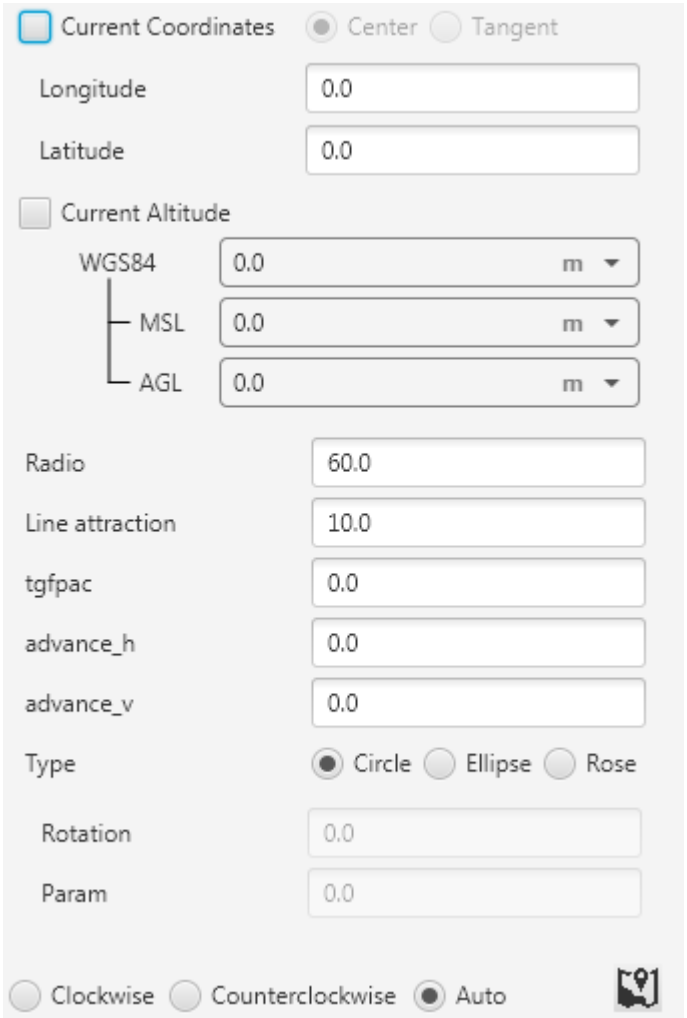
In order to configure the guidance, the following parameters must be entered:

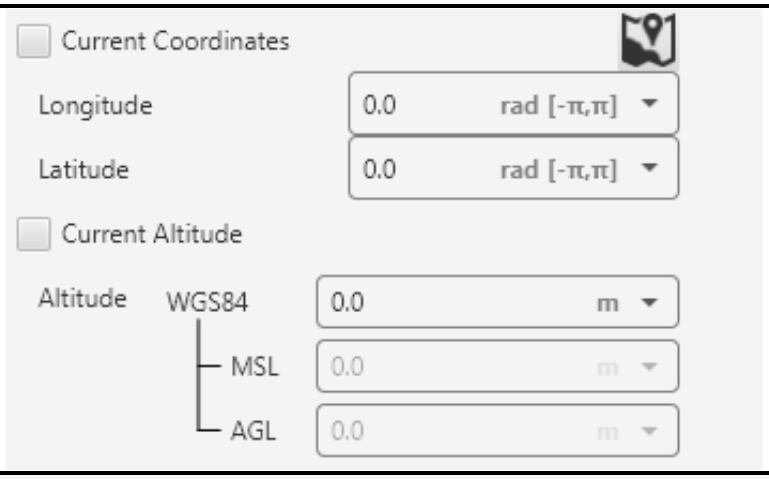
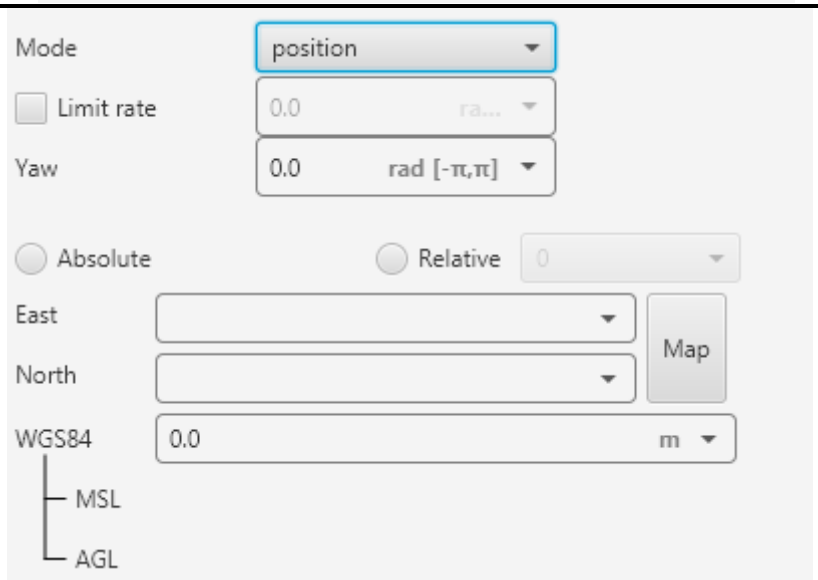
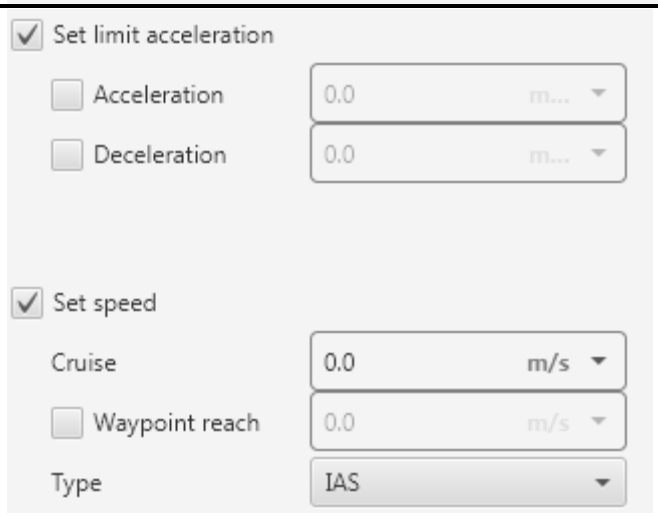
Value	Description
Name	Set a custom name for the control phase, to be displayed on Veronte Panel
Period	Enter a control step period for the control phase
Type	Select the guidance type from available, described below
Change	When “No Change” is selected, control parameters on phase entering will be maintained

Table 16: Guidance Settings

For each guidance type the following parameters are configurable:

Type	Interface
Hold: Maintain certain variables on the system **None:** Set variable value **Time:** Set a time tamp between an input and an output variable **Slope:** Set a ramp rate for changing form input variable to output variable **Ewma:** Exponential rate form input to output variable, enter tau parameter	

Loiter: Select loitering parameters and coordinates to perform the manoeuvre. **Position:** Enter position and altitude for the loitering centre **Radius:** Set loitering radius **Line attraction:** Force the platform to follow the desired track. Higher values means lower attraction **Tgfpac:** Altitude change rate **Advance_h /v:** Parameter for setting the guidance form tangent to line attraction **Circle:** Circular loiter **Eclipse:** Eclipse loiter - ***Rotation:*** angle in radians - ***Param:*** eccentricity (0-1) **Rose:** Rose loiter - ***Rotation:*** angle in radians - ***Param:*** number of petals	
Way: Select the waypoint to go on phase entering and control parameters. **Waypoint:** First waypoint to go **WLine: Line attraction:** Force the platform to follow the desired track. Higher values means lower attraction **Banking turn:** Desired platform backing on turn	

Hover: Maintain position and attitude. **Position:** Enter position and altitude for the hover centre	
Yaw: Yaw control. **Current:** Maintain current yaw **Fixed:** Set fxed yaw value **Heading:** Maintain current heading. **Position:** Point to a fixed position. **Limit rate:** Maximum yaw rate **Yaw:** Desired Yaw	
Hspeed: Speed control **Limits:** Set maximum acceleration and deceleration limits **Cruise:** Set cruise speed **WP Reach:** Set speed on waypoint reach	

Runway: Enter runway parameters for landing. **1 & 2:** Runway limits **Line attraction:** Force the platform to follow the desired track. Higher values means lower attraction	

Table 17: Control Type

4.2.4.2. Loop

On each phase, controller parameters can be set for each control channel defined on Veronte Configuration. Each one of them having the following status options:

Value	Description
Off	Disables the PID controller.
On	Enables the PID controller.
Fixed	Sets the control parameters to a fixed value.

Table 18: PID Control Status

PID Settings

When configuring a PID, up to three control loops can be configured, select on the combo box the desired option.

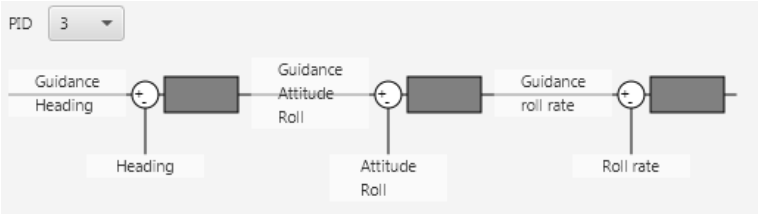


Figure 48: PID Architecture

For setting PID variables, select the variable to set and a list with available options will be displayed.

For setting the PID parameters click on the grey boxes and the PID diagram will be shown:

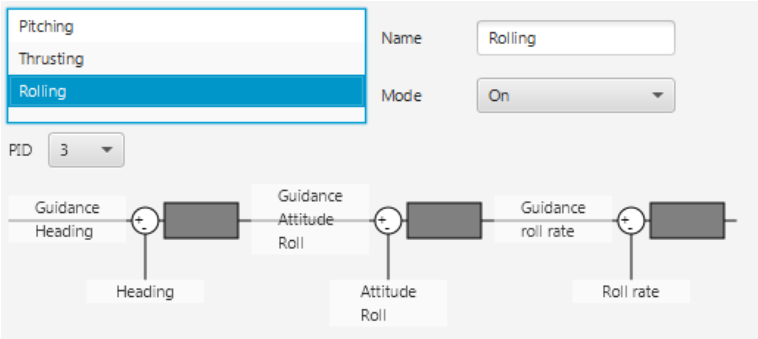


Figure 49: PID Diagram

For each block it is possible to configure the PID:

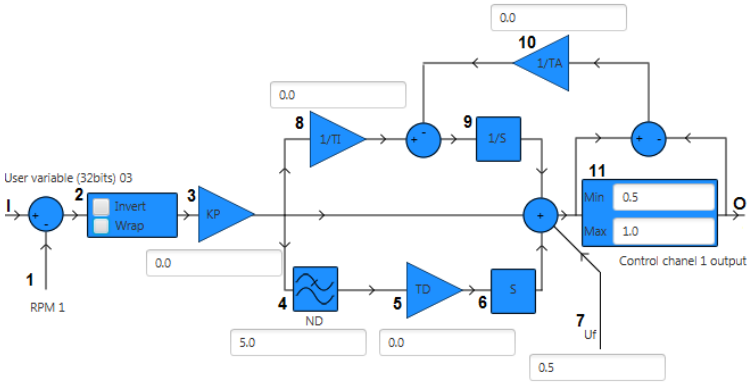


Figure 50: PID elements

Value	Description
I	Set Point
1	Measure
2	• **Invert:** Change error sign • **Wrap:** Wrap to pi [-π, π] It is used in some angular variables (radians) for avoiding numerical errors on the –π to π change and keep continuity of the error signal
3	Proportional gain
4	Discrete filter parameter
5	Derivative time parameter
6	Derivative
7	Constant value added to output
8	Inverse integral time parameter
9	Integral
10	Anti-windup parameter
11	Output bounds
O	Output

Table 19: PID Elements

Output values for PID controller refer to virtual control channels, units must coincide with servo trim configuration settings.

PID diagram represents the following PID model:

$$C = K_p\left(1 + \frac{1}{T_i}IF(z) + \frac{T_d}{\frac{T_d}{N} + DF(z)}\right)$$

K_p=proportional gain

T_i=Integrator time

T_d=Derivative time

N=Derivative filter constant

For the derivation and integration models, Trapezoidal and Backward Euler models have been integrated:

$$IF(z) = \frac{T_8}{2}\frac{z+1}{z-1} \qquad ND(z) = \frac{T_8 z}{2z-1}$$

$ND = \frac{T_d}{\tau}$ where τ is the is the time constant on a first order FPB. When ND is set to 0, the FPB is disabled.

Sampling time has already been integrated: $K_i = \frac{K_p}{T_i}$.

Initial block permits to invert the input signal or apply a wrapper, it is used for angles to be maintained between $\pm$ 180º.

On the output block it is possible to set the maximum and minimum values for the variable.

Exporting PIDs to other phases

Once it is considered that the PID is tuned, the user can easily export that PID in order to use it in other phases. To do so, just select *Copy* by right clicking on the desired PID and select the suitable phases.

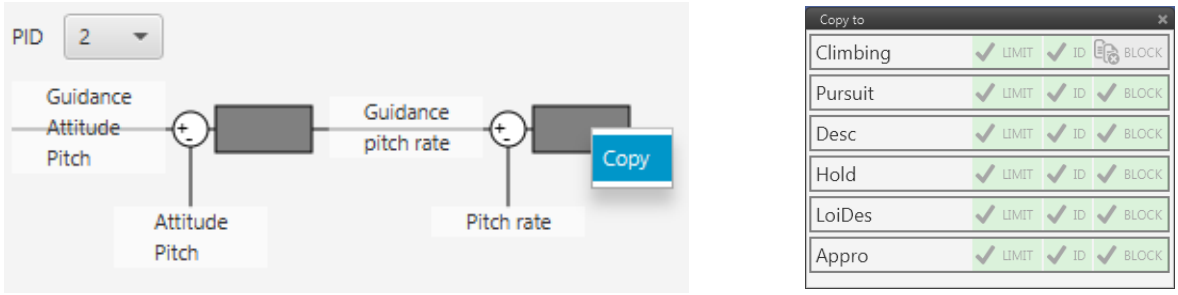


Figure 51: Copy Option

Fixed Settings

When fixed mode is selected the following diagram is displayed:

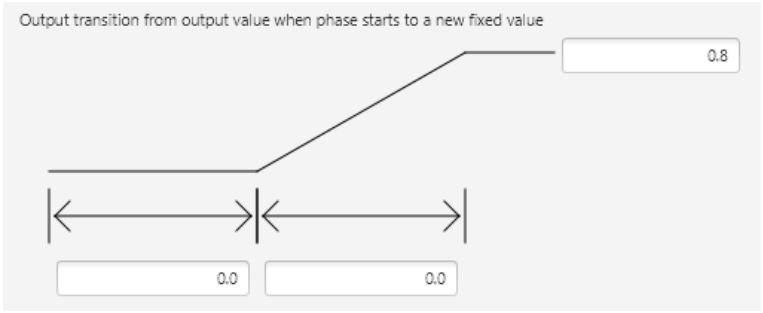


Figure 52: Fixed Value Settings

Three values must be entered, the remaining time in the starting conditions, the transition time and the variable final value.

4.2.4.3. Arcade Mode Settings

Arcade mode permits to have a simplified manual flight mode. The stick movements actuate directly over the control variables instead for a user friendly aircraft control.

Parameters are configured for each phase by setting values available when Show Arcade is selected.

Figure 53: Arcade Mode Settings

User can enter the affected control variables and the gain for each one. Select Integral for continuous variable value increase on joystick hold, or leave it unchecked for resetting the control variable value after joystick release.

4.2.4.1. TC Panel

Select the variables that will be accessible from the Veronte Panel.

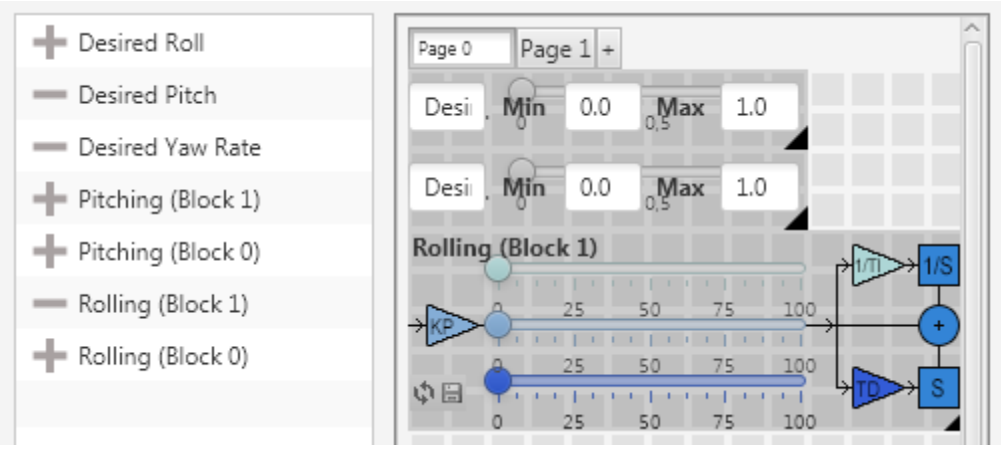


Figure 54: TC Panel

4.2.4.2. Envelop

Enter aircraft flight envelop, limits that will be never exceeded on the control.

Figure 55: Envelop

4.2.5. Modes

In this section, users can select the controller for every mode. The main idea is to set who is controlling the platform dynamics. The interface options are:

	Pitching ...	Thrustin...	Rolling (...	Yawing (...	Pitching ...	Thrustin...	Rolling (...	Yawing (...
Auto A	auto	auto	auto	auto	auto	auto	auto	auto
Manual M	rc	rc	rc	rc	auto	auto	auto	auto
G-Arcade G	auto	auto	auto	auto	arc	arc	arc	arc
Semi-Arcade S	auto	auto	auto	auto	arc	rc	arc	arc
Add								

Figure 56: Mode Settings

It is every common to find an automatic mode where all the dynamics are controlled by the autopilot. Likewise, the manual mode is completely controlled by the remote controller (*rc*). To change any of this options, click on the cell you would like to change and the next option will be set.

4.2.6. Navigation

Navigation parameters are configured on navigation tab. Being possible to configure accelerometers, gyroscopes, sensor measuring filters, angular speed estimation filters, state vectors and wind influence.

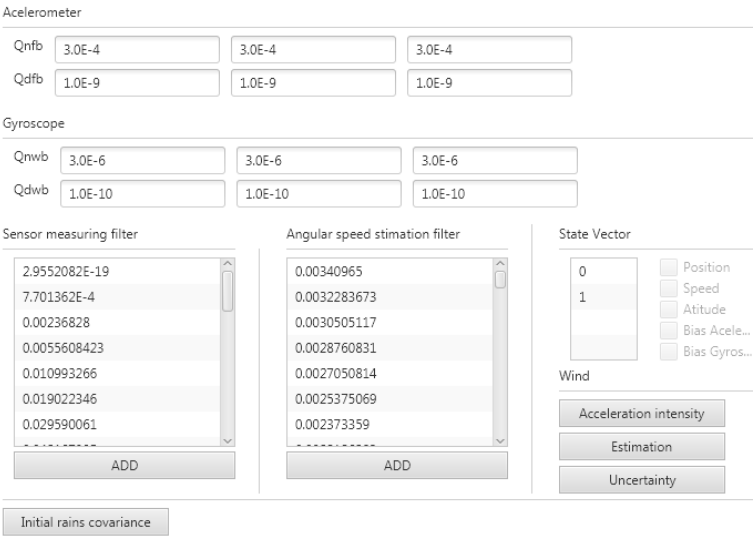


Figure 57: Navigation parameters

4.2.7. Automation

Automation configuration permits to set actions to be performed under predefined detected events.

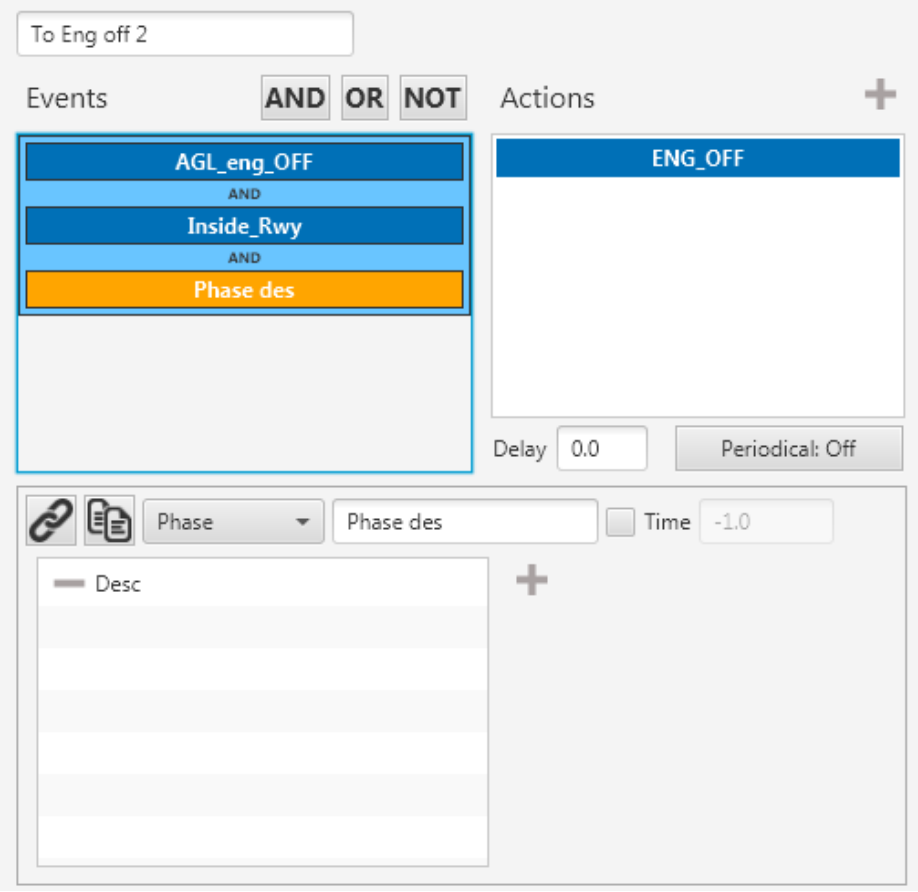


Figure 58: Automation Display

Automations are a combination of events and actions. All actions will be performed on event or an event combination triggering.

Delay is entered in seconds and permits to introduce a delay on the actions to take place.

Periodical button permits to configure actions to take place periodically during the time that the activation events are active, repeated each "x" time or distance. Actions will automatically stop once the event compliance stops.

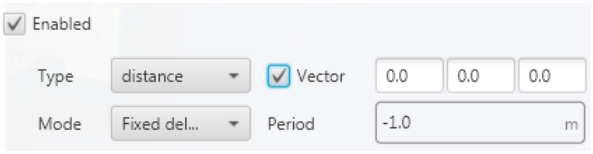


Figure 59: Setup – Automations –Periodical

Periodical actions can be configured in time or in distance, when enabled, actions associated to the automation will repeat at a fixed period in time or distance, distance period can be configured in distance over the ground or in distance in certain direction, by entering the vector.

Period can be set as a Fixed Delay (time between action activations) or as a Fixed Period (reference time for every action will be the first event activation).

When entering a new Event or Action it is possible to choose form one of the previously created on the system or to create a new one. Once created it is possible to configure it on the panel below. Common configuration options are:

Button	Description
	Select an action or event from the available in the system. When modifying an action or event it will be modified in all automations where it is in use.
	Clone an existing action or event creating a new one with same parameters configured on the start point.

Table 20: Setup – Automations

Following actions are available:

Type	Description
Output	Configure a GPIO output • **Off:** Set GPIO value to "0" • **On:** Set GPIO value to "1" • **Pulse On:** Set GPIO value to "1" for "x" seconds and end on "0" • **Pulse Off:** Set GPIO value to "0" for "x" seconds and end on "1"
Onboard log	Record onboard information on the User Log
Servo	Set a servo position to a predefined position for a given time.
Navigation	Set Navigation mode: • **Initial:** Navigation configuration on system startup. • **EKF:** Navigation configuration for operation, default configured for Stand By • **Simulation:** Simulation mode Simulation transitions permitted are: Initial to EKF or Initial to Simulation
Periodical	Configure timer for periodic actions. To be used as a periodic event.
Fly to	Fly to a waypoint, target waypoint will be selected on mission edition.
Phase	Change Control Phase to one of the configured.
Mode	Change flight mode to one of the configured.

Table 21: Setup - Automation - Actions

Activation events are:

Type	Description
Waypoint	Execute actions on waypoint arrival.
Variable	Select a range for any variable on the system.
Mode	Select the flight modes for the event to take effect.
Button	Configure a button to be displayed on Veronte panel.
Alarm	Select system fail detector.
Polygon	Execute actions when inside or outside a defined area.
Phase	Select flight phases in which the event will be active.
Timer	Select a preconfigured timer.

Table 22: Automation Activation Events

Events can be grouped on an automation introducing some logics:

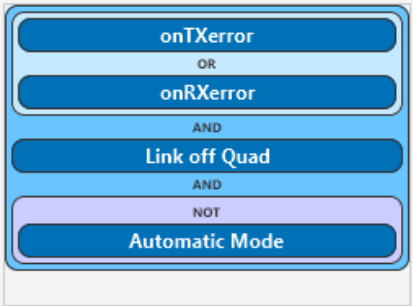


Figure 60: Automations – Event Logics

Logics	Description
AND	All events grouped on an AND should be accomplished simultaneously in order to activate the automation.
OR	One of the events in the group should be accomplished for activating the automation.
NOT	The event will be active meanwhile the event or event group is not accomplished.

Table 23: Automations – Event Logics

There is a “Time” parameter when configuring an event. This time refers to the time the event should be active in order to consider that the event has been accomplished. Enter “0” or a negative value in order to activate the automation immediately after the event has been accomplished.

4.2.8. Variables

4.2.8.1. System Variables

Names

Enter custom variable names for predefined variables on the system. Click on table and enter custom name for variable.

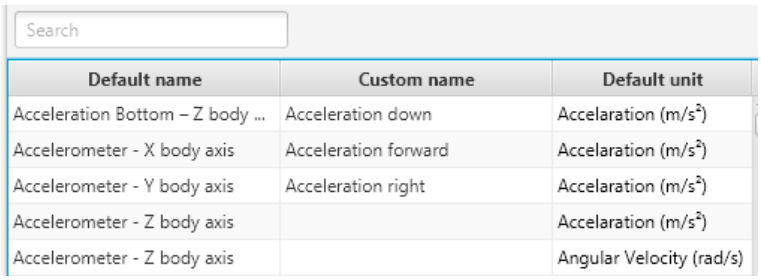
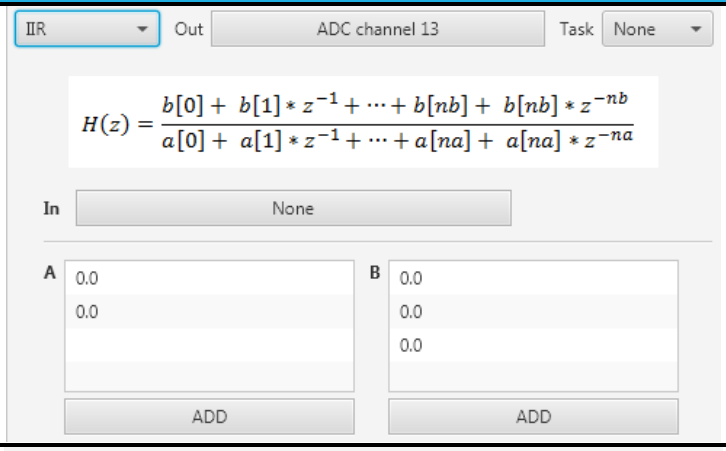
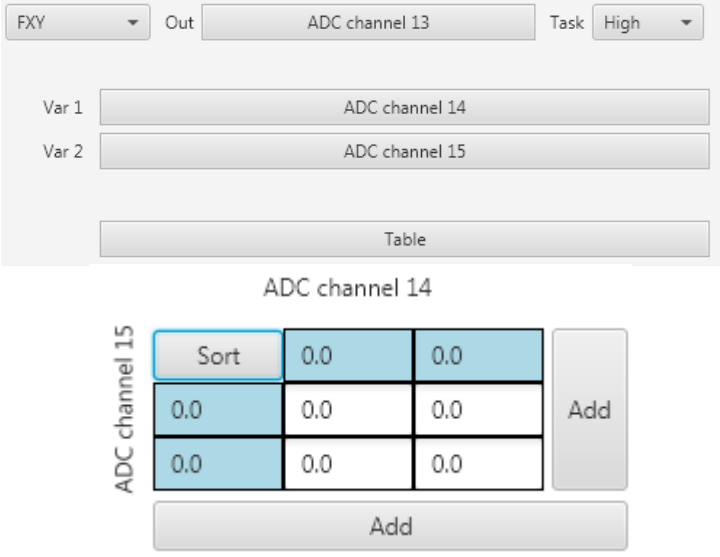
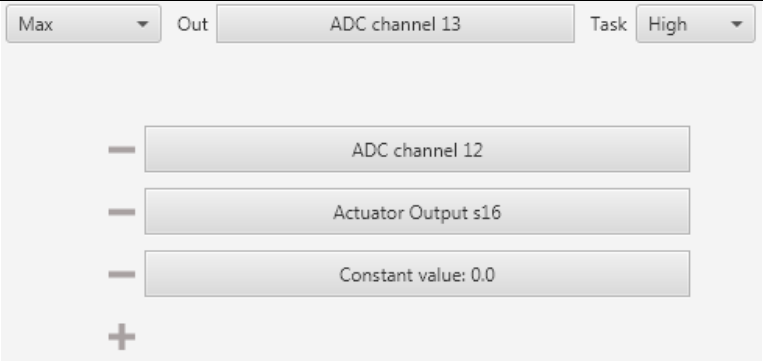


Figure 61: Variable name customization

Operations

It is possible to configure custom operations to be performed in Veronte by selecting the input and output variables and operation parameters.

Type	Interface
IIR: IIR digital filter, enter the parameters for filtering the variable value.	
FXY: FXY matrix, complete the table for setting an output value according to two input ones.	

Linear Expresion: Output variable acquires the value of the sume of input variables multiplied for a constant value.	
Max / Min: Output variable takes the value of the maximum / minimum value from the ones on the input variables / constants	
Wrap: Output variable is wrapped to keep value between upper and down limits.	

4.2.8.2. Telemetry

Telemetry controls permits to configure data to be stored or transmitted on the system. There are 4 main items that can be configured within this panel:

Type	Description
Data Link	Configures the variables to send throughout the datalink channel.
Log	Sets the variables to be stored on system Log.
User Log	User Log for custom applications.
Fast Log	Saves data at the maximum frequency available on the system. Recording time depends on the selected variables.

Table 24: Telemetry Configuration

Configuration display permits to enable the desired variables for each telemetry file and to set the maximum and minimum values together with precision for each one.

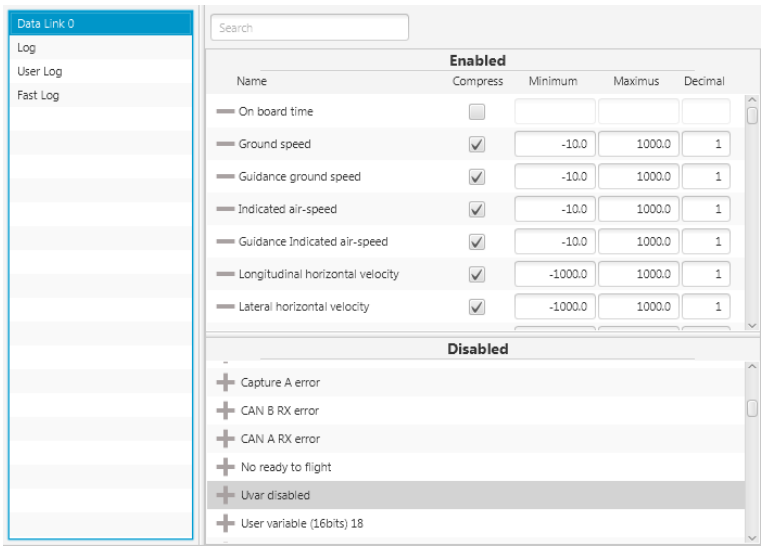


Figure 62: Setup – Telemetry

4.2.9. Panel

Configure Veronte Panel display options.

4.2.9.1. Short Phases

Configure the way control phases are displayed on Veronte Panel:

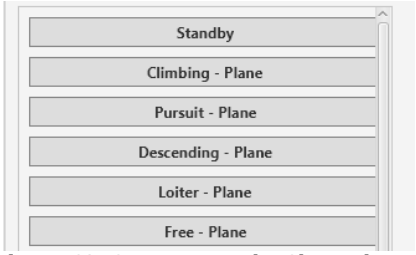


Figure 63: Setup – Panel – Short Phases

4.2.9.2. Checklist

A checklist is configurable for each flight phase. This checklist will be displayed on the Veronte Panel and must be completed prior to exiting from a phase.

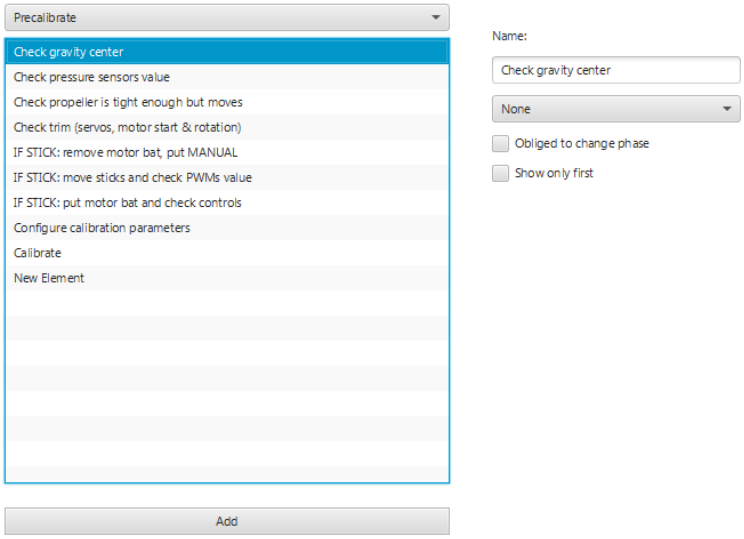


Figure 64: Checklist

Any custom test can be introduced to the checklist for performing customized checks; there are other system checks that can be included by selecting it form the combo box displayed. Main configurable items are described below:

Element	Description
Phase	Select the phase on which the checklist will be shown.
Name	Enter the checklist item name.
System checks	Select from the combo box preconfigured checklist elements.
Obliged to change phase	Select if required for phase change.
Show only first	Select for showing the checklist only once.

Table 25: Checklist Configuration

There are some preconfigured checklist items:

Element	Description
Atmosphere	Calibrate static pressure for altitude estimation (QNH)
Cparams	Enter sensor parameters for calibration
Calibrate	Start calibration (Required prior to Stand By)
Validate Mission	Check mission altitude
Asist GPS	Enter GPS position for quick GPS positioning
Test Servo	Test servos configured on stick
RTK	Enter control station GPS position for better RTK positioning

Table 26: Preconfigured Checklist

4.2.10. HIL

Refer to the HIL Simulator manual in order to configure XPlane parameters for simulation.

4.3. Tunnel UDP

The tunnel UDP allows the user to send data from Veronte autopilot to an external program or application. The system uses the **User Datagram Protocol (UDP)**.

4.3.1. UDP Tunnel menu

UDP Tunnel menu allows the user to select the IP and Port number to send the data from Veronte.

Figure 65: UDP Tunnel Config

4.3.2. UDP Tunnel file

Inside the folder containing Veronte Pipe, the user can find the file ***sa.tudp*** by following the following path:

\resources\UDPTunnel\sa.tudp

In this file we have several options to configure the data sent and format. Next, each of the parts of the file is explained:

Element	Description	Example
Head	User specified the head of UDP packet.	&HEAD 0201000000
LVARS	User can include JavaScript code to previously manage Veronte data.	L0 = false = L0?(u1_1_RVAR_1008 > 60) : (u1_1_RVAR_1008 < 70)
#OFFSET	Position data (in bytes) specified within the UDP package.	1, 2, 3, etc.
LONGITUD	Lengths of the data (in bytes).	1, 2, 4, etc.
MULT	Factor to multiply the input data.	0.01, 10, etc.
OFFSET	Factor to add to the input data.	-10, 100, etc.
TVAR	Type of the data of the output variable.	Float, UInt16, Byte, Int32, Bit
UAV	Address of the autopilot.	255, 1, 2, etc.
MCU	Microcontroller unit. Normally 0.	0, 1.
VERVAR	Type of the data of the impute variable.	RVAR, LVAR, UVAR, BIT, L_EQ, LIMIT, CUSTOM
ID	Number of the variable on Veronte autopilot. See ***Appendix 1***.	1, 2, 6, 1000, etc.
UNIT	Convert the unit of the output variable.	17 (rad to ºC).
DESC	Text to describe the data.	//Airspeed (Knots)

Table 27: UDP Configuration

5. WORKSPACE CONFIGURATION

Workspace settings allow user to customize any information to be displayed on the screen for monitoring the operation. Custom workspaces can be created, set any workspace as default in order to open it automatically on system start.

Telemetry toolbar is shown below.

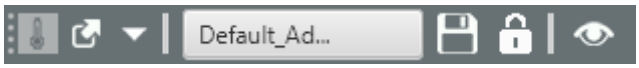


Figure 66: Telemetry Toolbar

	Load	Select the workspace to be displayed or create a new one.
	Save	For saving current telemetry configuration.
	Lock	Configured displays can be moved freely and resized along the screen. Press lock to avoid display free movement.
	Show	Display or hide workspace elements
	Details	Displays any configurable fields.

Table 28: Telemetry Toolbar

When creating a new workspace, the following options are available:

Workspace	Description
Empty	Creates an empty workspace.
Clone	Creates a copy of an existing workspace and permits user to edit it.
Merge	Creates a new workspace by merging any existing workspace.

Table 29: Workspace Creation

The following display items are configurable:

- **Map:** Configure map display items and create extra pop-up maps.
- **Gauge:** Select the variable to be displayed and configure the appearance.
- **Cam:** Configure displayable information on cam.
- **Advanced PFD:** Configure Primary Flight Display preferences.
- **Stick:** Configure virtual sticks for manual control.
- **Terrain:** Configure terrain profile display appearance.

Each display it permits to select the Veronte unit information to be displayed. Choose “Selected” to display telemetry information from selected Veronte. To select one Veronte unit, click on it at “Veronte panel” or “side panel”.

5.1. Map Display

Map widget permits to configure the background map, select from the available list for setting the main window map.

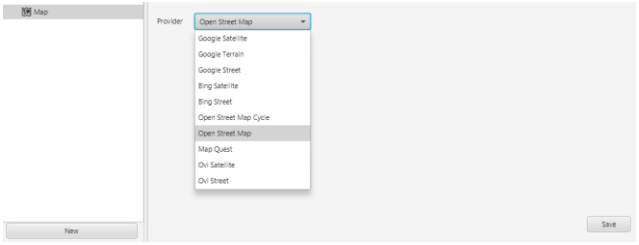


Figure 67: Map Settings

5.1.1. Custom Background Maps

Custom maps can be displayed in Veronte Pipe. It permits to include as many images as desired that will be displayed over the map.

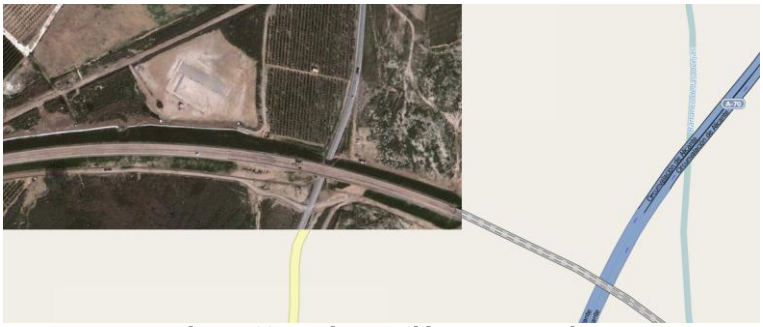


Figure 68: Background image example

In order to insert an image within the map, just drag the image and drop it on the map. A popup window will be displayed to position the image within the map. Click on save to go to the image manager where image coordinates can be entered manually.

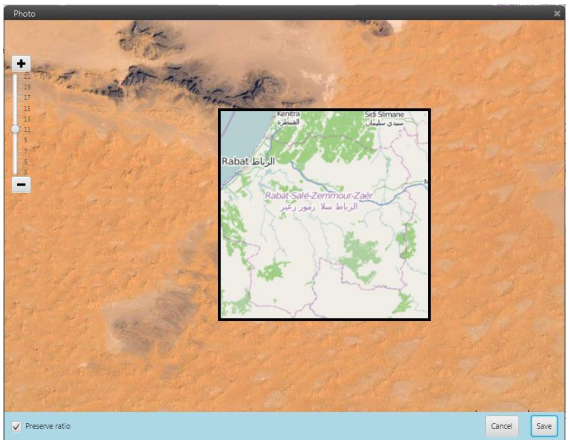


Figure 69: Background image positioning

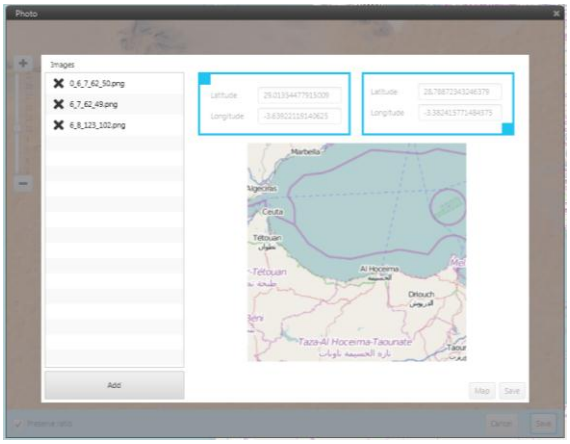


Figure 70: Background image manager

5.2. Gauge Display

Configure drag and drop displays for each telemetry variable and place it at any place on the screen.

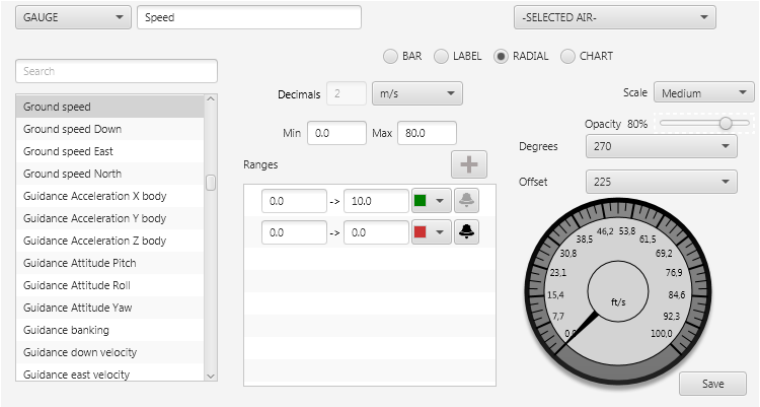
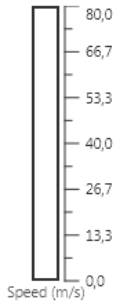
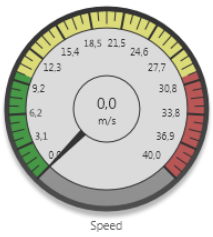


Figure 71: Gauge Configuration

In order to setup a gauge, select the variable to display from the available in the system and configure the display layout. Layout and colours are highly configurable, some gauge examples:

Bar	Label	Radial	Chart
			

5.3. Advanced Primary Flight Display

Primary flight display layout is highly configurable in colours and size. User can select the 2D and 3D visualization modes plus to display actuators and control channels.

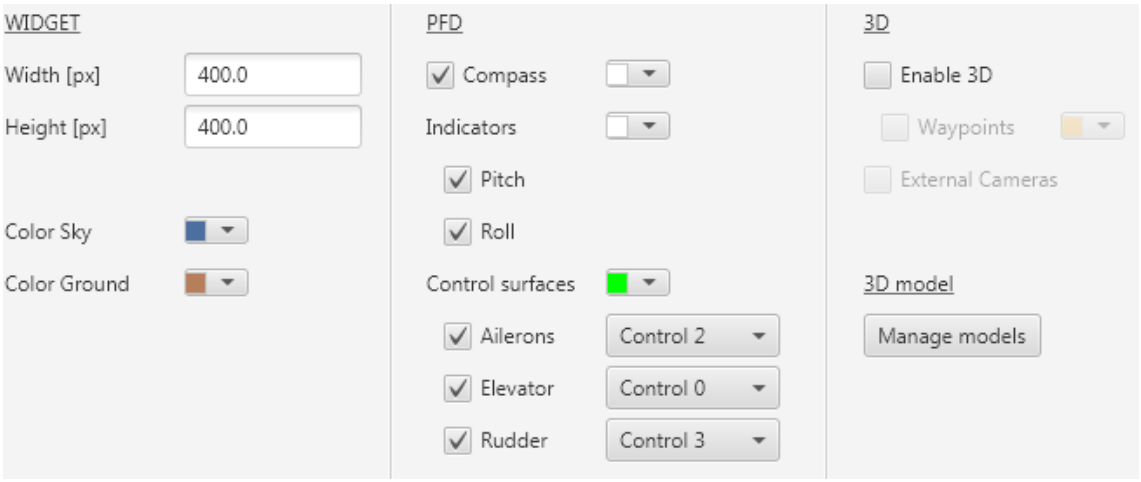


Figure 72:PFD Configuration

- WIDGET: user can define the widget size in pixels (width and height), sky and ground colours.

- PFD: user can decide if compass, indicators and surfaces are displayed, its colours and the control channels.

- 3D: allows to modify 3D options. If 3D visualization is enabled, waypoints and external cameras can be displayed.
    - By clicking the camera icon, user can select camera view: PFD (internal camera at cabin), UP BACK, BACK, FRONT, LEFT, RIGHT.
    - When an external camera is selected, it will be displayed a slide to change distance between the camera and the aircraft, and a 'MOVE CAMERA' checkbox, wich permits to move aorund the camera by dragging the mouse on the widget.

- 3D model: 'Manage models' button displays a configuration pannel to introduce the custom aircraft model to be displayed.
    - Open: it permits to select a STL file to be loaded.
    - Save: save user changes in a STL file.
    - Use this model: select the current model to be displayed on the widget.
    - Origin units: user can select origin file units. The model is real-scaled according to the terrain shown on the widget.
    - Size: percentage scale factor.
    - Axis max: axis length in meters.
    - Translate/rotate/camera: translate and rotate modify model orientation. Camera change the view displayed in Model 3D window. X,Y,Z buttons produce changes according to this axis. Default button resets any modification.

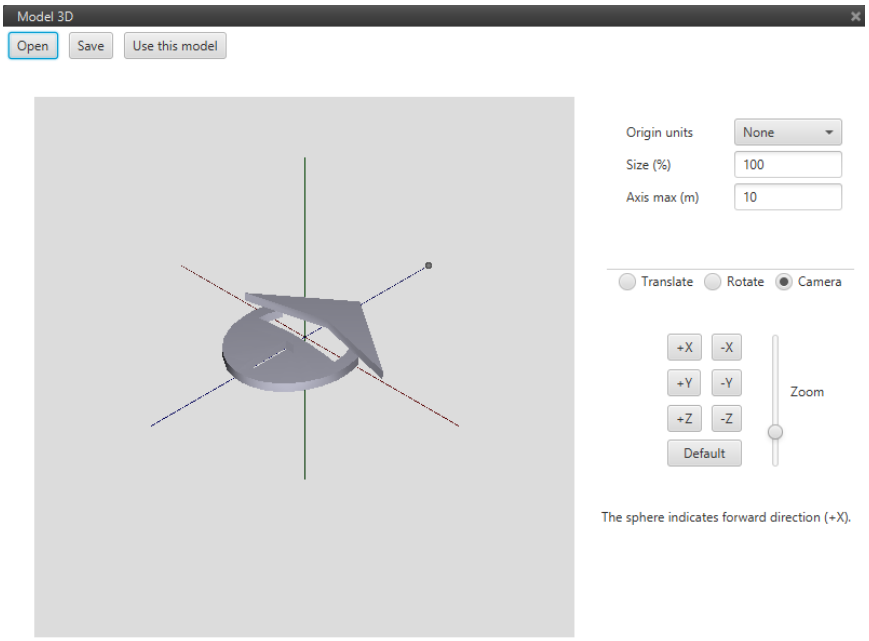


Figure 73: 3D Model

Some PFD display configurations are shown as an example:

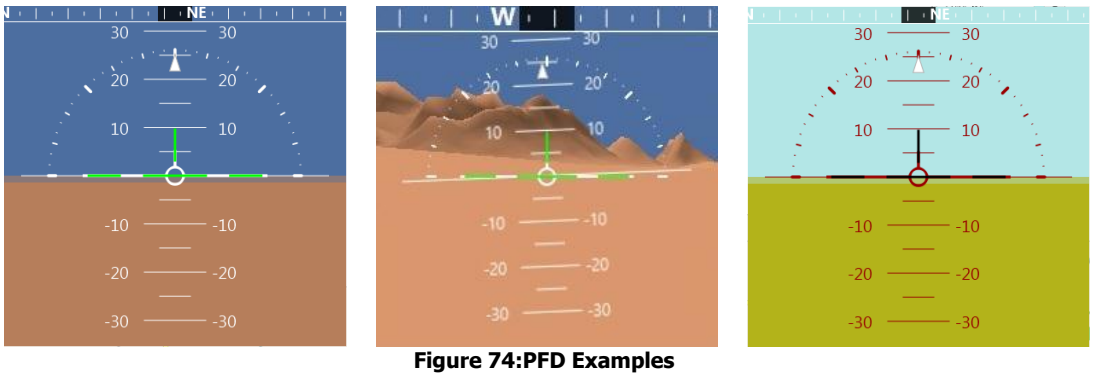


Figure 74:PFD Examples

5.4. Stick

Virtual sticks can also be created for manually control the control channels from the computer. Following setup options are available:

Item	Description
Scale Value	Select the scale to show on the stick.
Stick Channel	Select the channel to control with the stick.
Return	When selected the stick automatically returns to middle position on stick release.

Table 30: Stick Configuration

Configuration panel and drag and drop stick are shown below:

Figure 75: Stick Configuration

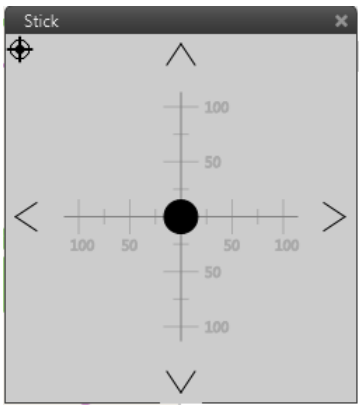


Figure 76: Stick Display

5.5. Cam

Cam display permits to configure a camera view on Veronte. Video source can be configured as an input device (Video capturer…) or as a network source.

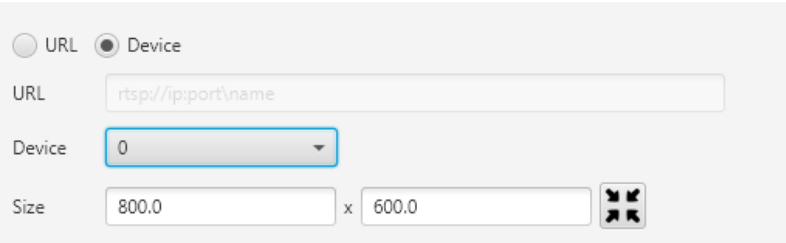


Figure 77:Camera display configuration

5.6. Terrain

Terrain display shows the terrain profile on the platform direction. Visualization configuration options are as follows:

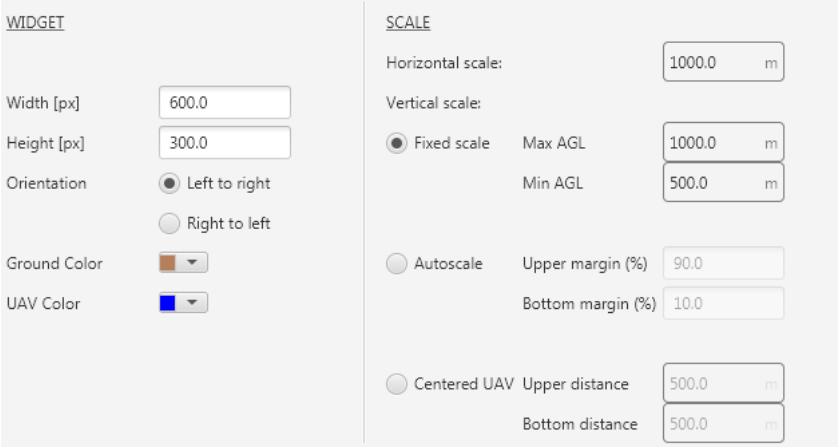


Figure 78: Terrain profile configuration

- WIDGET: user can define the widget size in pixels (width and height), ground and UAV colours, and the UAV ahead orientation (from left to right or the opposite).

- SCALE: horizontal and vertical scales can be configured.
  - Horizontal scale: terrain length to be displayed.
  - Vertical scale: there are three options:
    - Fixed scale: user selects Maximum and Minimum AGL scale limits.
    - Auto scale: terrain displayed will be auto scaled when UAV altitude reaches the upper or bottom margins stablished.
    - Centered UAV: user can define the upper and bottom distance which are represented.

6. FLIGHT PLAN

For operation planning, the mission toolbar must be used:

Figure 79: Mission Toolbar

Main functions available are:

	Open	Open a mission to edit
	Load	Select mission to edit
	Close	Close loaded mission
	Discard	Discard changes
	Save	Save edited mission
	Sync	Save mission on change
	Select	Select a group of waypoints or targets.
	Add WP	Add new waypoint on click position.
	Polygon	Introduce number of polygon sides and draw it on the map.
	Link	Create and edit links among waypoints.
	Irregular Area	Draw irregular areas on the map for association with polygon events
	Regular Area	Draw regular areas on the map for association with polygon events
	Circular Area	Draw circular areas on the map for association with polygon events
	Mapping	Draw a polygon for mapping applications.
	Ruler	Measure on map.

Table 31: Mission Toolbar

6.1. Waypoint Creation

Use the Add WP tool and press on the map for creating waypoints, a display will appear for entering custom parameters:

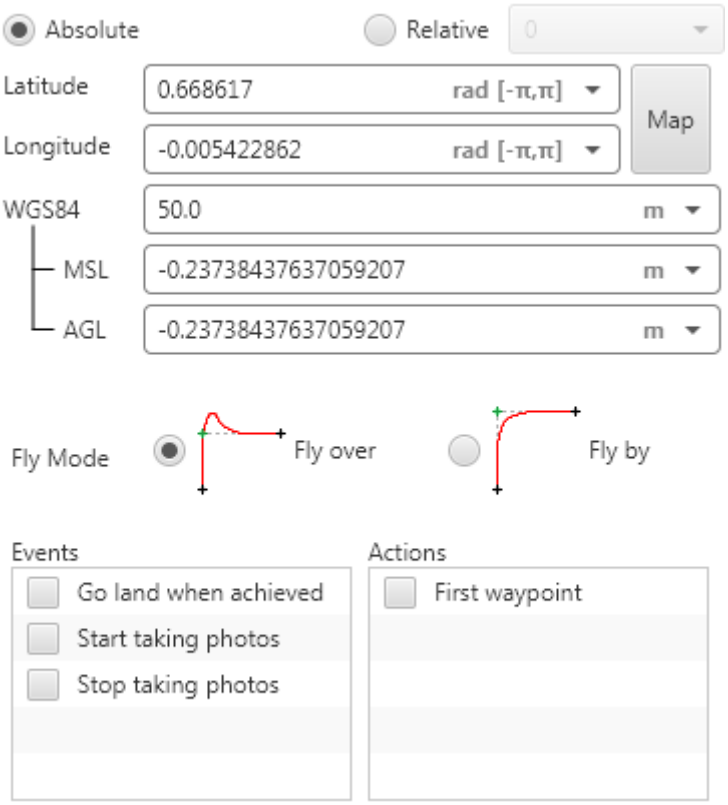


Figure 80: Waypoint Parameters

Item	Description
Mode	• **Absolute:** Fixed GPS position • **Relative:** Relative position to a predefined interest point (any Veronte equipped device)
Position	GPS coordinates, press map to select on map
Altitude	• **WGS84:** Altitude over the ellipsoid • **MSL:** Mean Sea Level altitude • **AGL:** Above Ground Level
Fly mode	Waypoint achievement mode
Events	Waypoint events configured on automations, mark to activate event on reach
Actions	WP actions configured on automations, mark to start action on reach

Table 32: Waypoint

For moving waypoints, drag it to the desired position. For editing other parameters double-click will display editable fields.

For regular polygon drawing, select the polygon tool and enter the number of desired waypoints then click on the map for drawing:

Figure 81: Polygon Creation

After the waypoints have been created, it can be joined creating the desired route with the link tool.

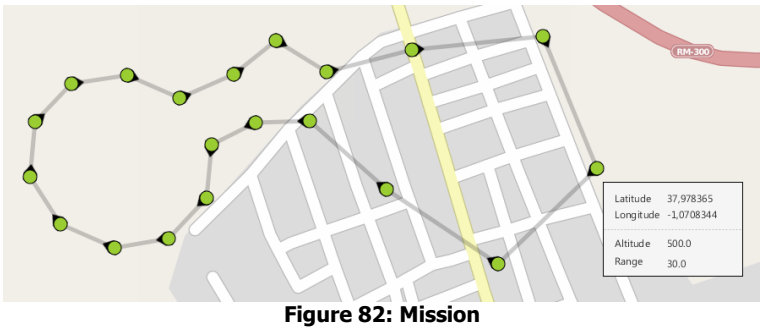


Figure 82: Mission

⚠ **Note:** Each waypoint can have multiple entries but just one output.

6.2. Mapping Tool

Mapping tool permits to draw a polygon on the map and configure camera parameters in order to automatically generate a mapping mission. Select the mapping tool and a display will be shown in order to create a new mission or select one mapping mission already created.

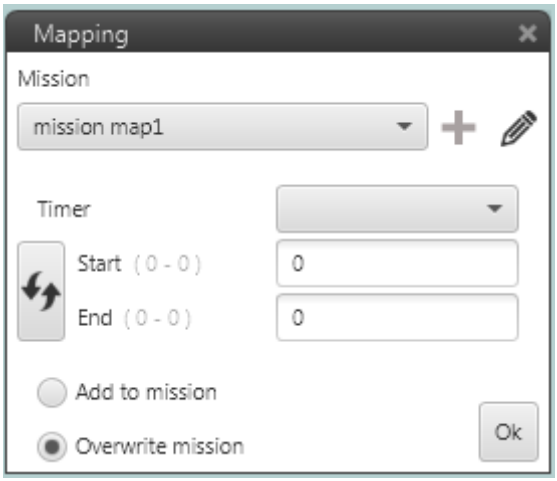


Figure 83: Mapping Mission 1

For creating a new mission, select the desired area for mapping:

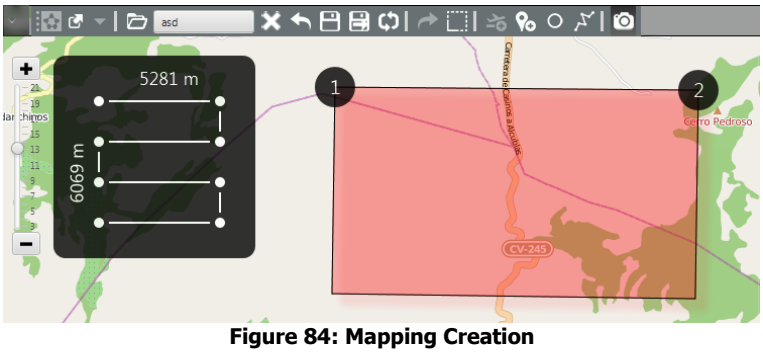


Figure 84: Mapping Creation

Enter the requested parameters so the mission can automatically be generated:

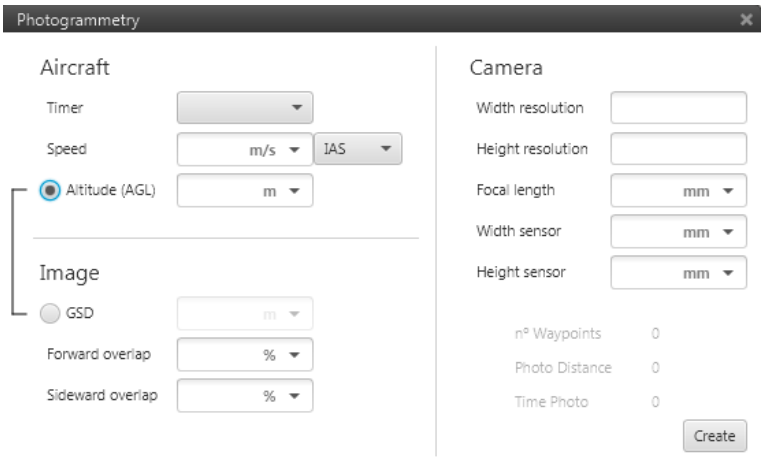


Figure 85: Mapping Parameters

Click on crate and the mission will be generated:

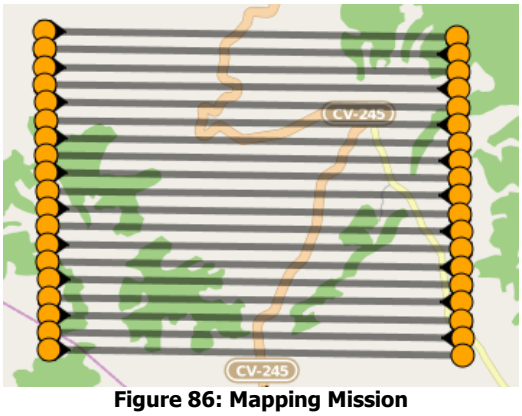


Figure 86: Mapping Mission

Once the mapping mission has been generated, the complete mission or the selected part can be included to the mission on Veronte. Select if the mission must be added to the existing mission (selected on the mission toolbar) or if it must be overwritten and press “Accept” to save it.

6.3. Terrain Profile

In order to display terrain profile options click on the details button on the Mission Toolbar. This panel permits to configure the zone of operation so the terrain data and magnetic field data from the operation zone. Terrain and magnetic field information are automatically loaded on mission generation but for some operations it may be interesting to do it manually.

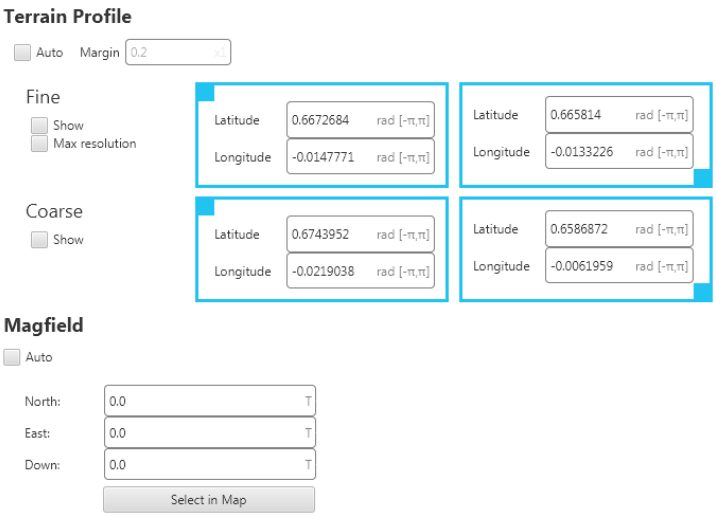


Figure 87: Terrain and Magnetic Field data

7. OPERATION

Once both Veronte units, the one on the control station and the one onboard, are configured and the mission has been loaded to the aircraft, the system is ready to start the mission. A list with linked Veronte units is displayed on the side panel. This display shows information and warnings.

Figure 88: Side Panel

Click on any Veronte to display Veronte Panel; it permits to control any telecommand actions.

Figure 89: Veronte Panel

Current phase is marked in green, select one of the blue phases to change to phase manually. In order to change phases all required checklist elements must be completed. In order to enter a phase there are two options. By clicking on the phase name the system will enter on the phase with the preconfigured parameters, click on the settings button on the right for entering to the flight phase changing the phase parameters. The view icon enables the visualization of the phase on the screen.

Phase parameters can also be configured on the control tab on the setup menu. Dependencies between phases and automatic phase transitions are configured on the automations panel.

During the operation, the following actions can be performed:

- **Flight monitoring:** Flight data can be monitored on the control station using telemetry displays. Telemetry display configuration can be edited during the flight.
- **Edit mission:** Mission can be edited prior or during the flight.
- **Change phase:** Phases permit to set the vehicle configuration to a specific performance. Click on a phase to initiate this phase.

- **Activate manual / assisted manual modes:** By pressing the preconfigured joystick button or selecting manual in Veronte panel, it is possible to control the aircraft in manual mode. Once the manual mode is deactivated it will continue in automatic mode, continuing with preconfigured route.
- **Abort mission:** ´Go Home´ button can be configured to appear in the Veronte panel. It can be configured on the automations panel.

During the operation it is possible to adjust the controller parameters, it can be done directly on Setup – Control, working directly on the PID parameters or can be done in the Veronte Panel, by using the shortcuts configured on the Setup – Control. On this panel it is possible to configure sliders to be active on the Veronte Panel.

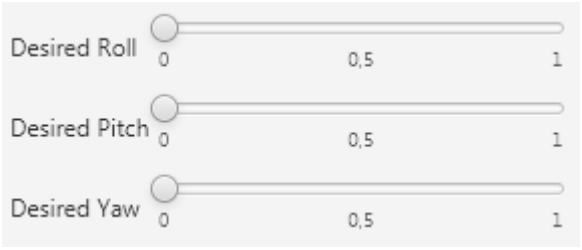
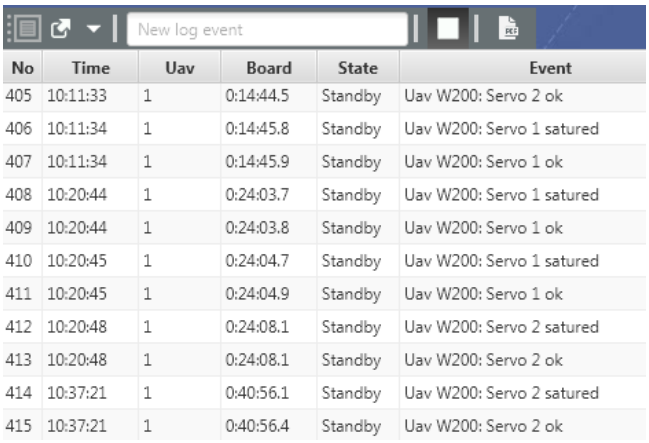


Figure 90: Veronte Panel tuning shortcut

Note: Control parameters set from the Veronte Panel are only applicable to the current operation. These data will not be stored for future operations. In order to save these parameters on the system it can be done on the Veronte Autopilot setup.

8. Log

Log toolbar shows recorded events and permits to introduce custom events to be saved. Introduce event information and press enter to record it on the log.



No	Time	Uav	Board	State	Event
405	10:11:33	1	0:14:44.5	Standby	Uav W200: Servo 2 ok
406	10:11:34	1	0:14:45.8	Standby	Uav W200: Servo 1 satured
407	10:11:34	1	0:14:45.9	Standby	Uav W200: Servo 1 ok
408	10:20:44	1	0:24:03.7	Standby	Uav W200: Servo 1 satured
409	10:20:44	1	0:24:03.8	Standby	Uav W200: Servo 1 ok
410	10:20:45	1	0:24:04.7	Standby	Uav W200: Servo 1 satured
411	10:20:45	1	0:24:04.9	Standby	Uav W200: Servo 1 ok
412	10:20:48	1	0:24:08.1	Standby	Uav W200: Servo 2 satured
413	10:20:48	1	0:24:08.1	Standby	Uav W200: Servo 2 ok
414	10:37:21	1	0:40:56.1	Standby	Uav W200: Servo 2 satured
415	10:37:21	1	0:40:56.4	Standby	Uav W200: Servo 2 ok

Figure 91: Log Toolbar

Record button permits to stop capturing log information. By clicking on REC, a new log saving will start.

It is possible to generate a PDF reports containing saved log information. Click on the “Report” icon and enter requested information to generate the report.

Figure 92: Report Information

9. POST-FLIGHT

Once the mission is finished, the operator can download telemetry data from Veronte to perform a virtual tour. Use the post flight toolbar:

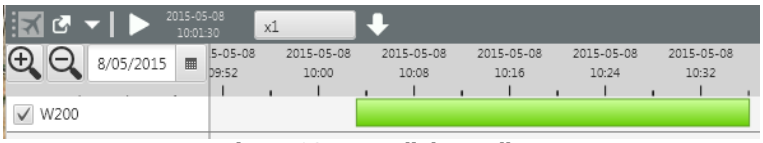


Figure 93: Post Flight Toolbar

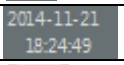
	Play / Pause	Manage tour play.
	**Time**	Control the time progress.
	Speed	To speed up the tour.
	Export	Download Veronte files and export data

Table 33: Post Flight Toolbar

9.1. Data export

Flight data stored in Veronte Pipe is saved at a low frequency, in order to improve the tour accuracy; it is possible to download the information on the autopilot by using the download button. This panel permits also to erase data from both Veronte Autopilot and the system.

Select the Veronte unit for data downloading and choose the flight files to be download. Right panel will show file download progress.

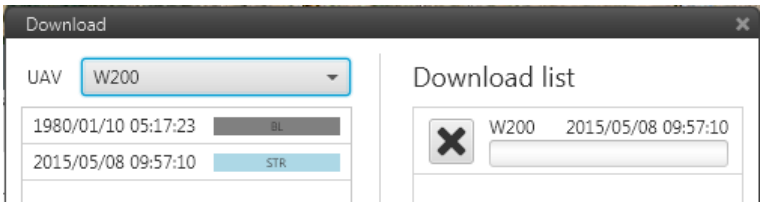


Figure 94: Data Export

When downloading ".BIN" files, the information on the autopilot is loaded into the PC, increasing the data accuracy recorded on the PC during the flight.

Once ".BIN" data has been imported to the PC, it is possible to export a CSV file in order to analyse data on any other software. This CSV file uses ";" for data separation and "," for decimal indication.

9.2. Tour

Flight data can be played on Veronte Pipe permitting to display all available flight information as done during the flight.

In order to play a tour, select the date and mark the Veronte Autopilot information to be played, flight data available will be shown on the timeline.

10. APPENDIX 1

The number ID of the most important variables of the Veronte autopilot and their description are shown in the following table:

Type	ID	Description
RVAR	0	Desired IAS (Indicated Air Speed)
	1	IAS (Indicated Air Speed)
	2	Desired TAS (True Air Speed)
	3	TAS (True Air Speed)
	4	Desired GS (Ground Speed)
	5	GS (Ground Speed)
	6	Desired Heading
	7	Heading
	8	Desired Flight Path Angle
	9	Flight Path Angle
	10	Desired Bank
	11	Bank
	12	Desired Yaw
	13	Yaw
	14	Desired Pitch
	15	Pitch
	16	Desired Roll
	17	Roll
	18	Desired Along-Track Position Error
	19	Along-Track Position Error
	20	Desired Cross-Track Error
	21	Cross-Track Error
	22	Desired Vertical Error
	23	Vertical Error
	24	MSL (Height Above Mean Sea Level) - Altitude
	25	AGL (Above Ground Level) – Height
	26	Desired Roll Rate
	27	Roll Rate
	28	Desired Pitch Rate
	29	Pitch Rate
	30	Desired Yaw Rate

	31	Yaw Rate
	32	Desired Forward Acceleration – X body axis
	33	Forward Acceleration – X body axis
	34	Desired Right Acceleration – Y body axis
	35	Right Acceleration – Y body axis
	36	Desired Bottom Acceleration – Z body axis
	37	Acceleration Bottom – Z body axis
	38	Desired RPM
	39	RPM
	40-48	Control Output u1-u9
	51	Time since hardware start-up
	52	Longitude
	53	Latitude
	54	WGS84 Elevation (Height Over The Ellipsoid)
	55	GS (Ground Speed) North
	56	GS (Ground Speed) East
	57	GS (Ground Speed) Down
	58	Sensor IAS (Indicated Air Speed)
	59	Angle Of Attack – AoA
	60	Sideslip
	61	Accelerometer - X body axis
	62	Accelerometer - Y body axis
	63	Accelerometer - Z body axis
	64	Gyroscope - X body axis
	65	Gyroscope - Y body axis
	66	Gyroscope - Z body axis
	67	Magnetometer - X body axis
	68	Magnetometer - Y body axis
	69	Magnetometer - Z body axis
	70	Power Input
	71	Analog Input
	82	Pitot Dynamic Pressure
	83	Barometric Static Pressure
	84	Internal Temperature
	94-105	PWM 1-12
	108	Radar AGL (Above Ground Level) – Height
	109	Radar Ground Speed Up
	112-127	Stick Input r1-r16
	128-143	Stick Input y1-y16

	150	Used Memory Space
	151	Free Memory Space
	180-189	Clock 1-10
	190	Desired GS (Ground Speed) North
	191	Desired GS (Ground Speed) East
	192	Desired GS (Ground Speed) Down
	193	Front GS (Ground Speed)
	194	Lateral GS (Ground Speed)
	195	Desired Front GS (Ground Speed)
	196	Desired Lateral GS (Ground Speed)
	202	GPS ECEF Position X
	203	GPS ECEF Position y
	204	GPS ECEF Position z
	205	GPS Velocity North
	206	GPS Velocity East
	207	GPS Velocity Down
	208	Desired MSL (Height Above Mean Sea Level) - Altitude
	209	Desired AGL (Above Ground Level) – Height
	210	Desired WGS84 Elevation (Height Over The Ellipsoid)
	211	Velocity - X body axis
	212	Velocity - Y body axis
	213	Velocity - Z body axis
	214	GPS Accuracy
	215	GPS Time of Week
	216	Estimated Dynamic Pressure
	217	Barometric Pressure at Sea Level (QNH)
	220-228	Stick Input u1-u9
	229-238	Stick Input d1-d9
	272	Longitudinal (Forward) Load Factor - X body axis
	273	Lateral (Right) Load Factor – Y body axis
	274	Vertical (Bottom) Load Factor - Z body axis
	275	Desired Longitudinal (Forward) Load Factor - X body axis
	276	Desired Lateral (Right) Load Factor – Y body axis
	277	Desired Vertical (Bottom) Load Factor - Z body axis
	278	RX Datalink Error Rate
	279	TX Datalink Error Rate
	292	Accelerometer bias - X body axis
	293	Accelerometer bias - Y body axis
	294	Accelerometer bias - Z body axis

	295	Gyroscope bias - X body axis
	296	Gyroscope bias - Y body axis
	297	Gyroscope bias - Z body axis
	300-331	Actuator Output s1/32
	400-431	Distance to Object of Interest 1 - 32
	800	Wind Velocity North
	802	Wind Velocity East
	803	Wind Velocity Down
	804	Wind Velocity North Estimation Covariance
	900-999	X-plane simulation variables
	1000-1099	Custom Variable 1 (single precision) 1 - 100
	2000	No selected variable
BIT	**0**	No code value
	3	GPS navigation code
	4	Fdr not writing code
	5	Ready to fly code
	6	File system code
	8	Georeference code
	9	CAN A RX code
	10	CAN B RX code
	11	CAP A code
	12	CAP B code
	13	SCI A code
	14	SCI B code
	15	SCI C code
	16	McBSP (Multichannel buffer) code
	17	Stick receive watchdog
	18	CAN A TX code
	19	CAN B TX code
	20-31	SERVO 1 -12 code
	32	EKF: Cholesky inverse code
	33	EKF: Inverse; condition number code
	35	System general start up BIT code
	53	Power A BIT code
	54	Power B BIT code
	62	Task 0 real time error
	63	Task 1 real time error
	64	Task 2 real time error
	65	Task 3 real time error

	66	Task 4 real time error
	67	Calibration step not completed yet
	1000-1999	User bit
	2000	No selected BIT
UVAR	**0**	Control Mode
	1	Mission Phase ID
	2 -17	ADC Channel 1-16
	18	Next Waypoint
	19	Last Achieved Waypoint
	20-51	GPS Satellite
	52	Radar Status
	900-909	Simulation variables
	1000-1099	Custom Variable 1-100 (16 bits)
STR	**0**	Link quality
	1	Guidance path currently active
	2	Go home mitigation status
	3	Parachute mitigation status
	4	Set auto mitigation status
	5	Climb mitigation status
	6	Cut engines mitigation status
	7	Link quality of his pair
	9	Position
	10-41	Object of interest i